

APPENDIX

PRO7000 DC Motor Operator
Manual forces, automatic limits
New learn switch for learning the limits

Code based on Flex GDO

Notes:

- Motor is controlled via two Form C relays to control direction
- Motor speed is controlled via a fet (2 IRF540's in parallel) with a phase control PWM applies.
- Wall control (and RS232) are P98 with a redundant smart button and command button on the logic board

Flex GDO Logic Board

Fixed AND Rolling Code Functionality
Learn from keyless entry transmitter
Posi-lock

Turn on light from broken IR beam (when at up limit)

Keyless entry temporary password based on number of hours or number of activations. (Rolling code mode only)

GDO is initialized to a 'clean slate' mode when the memory is erased. In this mode, the GDO will receive either fixed or rolling codes. When the first radio code is learned, the GDO locks itself into that mode (fixed or rolling) until the memory is again erased.

Rolling code derived from the Leaded67 code
Using the 8K zilog 233 chip
Timer interrupt needed to be 2X faster

Revision History

Revision 1.1:

- Changed light from broken IR beam to work in both fixed and rolling modes.
- Changed light from IR beam to work only on beam break, not on beam block.

Revision 1.2:

- Learning rolling code formerly erased fixed code. Mode is now determined by first transmitter learned after radio erase.

Revision 1.3:

- Moved radio interrupt disable to reception of 20 bits.
- Changed mode of radio switching. Formerly toggled upon radio error, now switches in pseudo-random fashion depending upon value of 125 ms timer.

Revision 1.4:

- Optimized portion of radio after bit value is determined. Used relative addressing to speed code and minimize ROM size.

Revision 1.5:

- Changed mode of learning transmitters. Learn command is now light-command, learn light is now light-lock, and learn open/close/stop is lock-command. (Command was press light, press command, release light, release command, worklight was press light, press command, release command, release light, o/c/s was press lock, press command, release command, release lock. This caused DOG2 to reset)

Revision 1.6:

- Light button and light transmitter now ignored during travel.
Switch data cleared only after a command switch is checked.

Revision 1.7:

- Rejected fixed mode (and fixed mode test) when learning light and open/close/stop transmitters.

Revision 1.8:

- Changed learn from wall control to work only when both switches are held. Modified force pot. read routine (moved enabling of blank time and disabling of interrupts). Fixed mode now learns command with any combination of wall control switches.

Revision 1.9:

- Changed PWM output to go from 0-50% duty cycle. This eliminated the problem of PWM interrupts causing problems near 100% duty cycle.
THIS REVISION REQUIRES A HARDWARE CHANGE.

Revision 1.9A:

- Enabled ROM checksum. Cleaned up documentation.

Revision 2.0:

- Blank time noise immunity. If noise signal is detected during blank time the data already recieved is not thrown out. The data is retained, and the noise pulse is identified as such. The interrupt is enabled to continue to look for the sync pulse.

Revision 2.0A:

- On the event that the noise pulse is of the same duration as the sync pulse, the time between sync and first data pulse (inactive time) is measured. The inactive time is 5.14ms for billion code and 2.4ms for rolling code. If it is determined that the previously received sync is indeed a noise pulse, the pulse is thrown out and the micro continues to look for a sync pulse as in Rev. 2.0.

Revision 2.1:

- To make the blank time more impervious to noise, the sync pulses are differentiated between. Fixed max width is 4.6ms, roll max width is 2.3ms. This is similar to the inactive time check done in Rev.2.0A.

Revision 2.2:

- The worklight function; when the IR beam is broken and the door is at the up limit the light will turn on for 4.5 min. This revision allows the worklight function to be enabled and disabled by the user. The function will come enabled from the factory. To disable, with the light off press and hold the light button for 7 sec. The light will come on and after 7 sec. the function is disabled the light will turn off. To enable the function, turn the light on, release the button, then press and hold the light button down for 7 sec. The light will turn off and after the function has been enable in 7 sec. the light will turn on.

Revision 3.0:

- Integrated in functionality for Siminor rolling code transmitter. The Siminor transmitter may be received whenever a C code transmitter may be received. Siminor transmitters are able to perform as a standard command or as a light control transmitter, but not as an open/close/stop transmitter.

Revision 3.1:

- Modified handling of rolling code counter (in mirroring and adding) to improve efficiency and hopefully kill all short cycles when a radio is jammed on the air.

PRO7000

Revision 0.1:

- Removed physical limit tests
- Disabled radio temporarily
- Put in sign bit test for limits
- Automatic limits working

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; Revision 0.2:
; -- Provided for traveling up when too close to limit
;
; Revision 0.3:
; -- Changed force pot. read to new routine.
; -- Disabled T1 interrupt and all old force pot. code
; -- Disabled all RS232 output
;
; Revision 0.4:
; -- Added in (veerrrry) rough force into pot. read routine
;
; Revision 0.5:
; -- Changed EEPROM in comments to add in up limit, last operation, and
;   down limit.
; -- Created OnePass register
; -- Added in limit read from nonvolatile when going to a moving state
; -- Added in limit read on power-up
; -- Created passcounter register to keep track of pass point(s)
; -- Installed basic wake-up routine to restore position based on last state
;
; Revision 0.6:
; -- Changed RPM time read to routine used in P98 to save RAM
; -- Changed operation of RPM forced up travel
; -- Implemented pass point for one-pass-point travel
;
; Revision 0.7:
; -- Changed pass point from single to multiple (no EEPROM support)
;
; Revision 0.8:
; -- Changed all SKIPRADIO loads from 0xFF to NOEECOMM
; -- Installed EEPROM support for multiple pass points
;
; Revision 0.9:
; -- Changed state machine to handle wake-up (i.e. always head towards
;   the lowest pass point to re-orient the GDO)
;
; Revision 0.10:
; -- Changed the AC line input routine to work off full-wave rectified
;   AC coming in
;
; Revision 0.11:
; -- Installed the phase control for motor speed control
;
; Revision 0.12:
; -- Installed traveling down if too near up limit
; -- Installed speed-up when starting travel
; -- Installed slow-down when ending travel
;
; Revision 0.13:
; -- Re-activated the C code
;
; Revision 0.14:
; -- Added in conditional assembly for Siminor radio codes
;
; Revision 0.15:
; -- Disabled old wall control code
; -- Changed all pins to conform with new layout
; -- Removed unused constants
; -- Commented out old wall control routine
; -- Changed code to run at 6MHz
;
; Revision 0.16
; -- Fixed bugs in Flex radio
;
; Revision 0.17
; -- Re-enabled old wall control. Changed command charging time to 12 ms
;   to fix FMEA problems with IR protectors.
;
; Revision 0.18

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; -- Turned on learn switch connected to EEPROM clock line
;
; Revision 0.19
; -- Eliminated unused registers
; -- Moved new registers out of radio group
; -- Re-enabled radio interrupt
;
; Revision 0.20
; -- Changed limit test to account for "lost" position
; -- Re-wrote pass point routine
;
; Revision 0.21
; -- Changed limit tests in state setting routines
; -- Changed criteria for looking for lost position
; -- Changed lost operation to stop until position is known
;
; Revision 0.22:
; -- Added in L A C state machine to learn the limits
; -- Installed learn-command to go into LAC mode
; -- Added in command button and learn button jog commands
; -- Disabled limit testing when in learn mode
; -- Added in LED flashing for in learn mode
; -- Added in EVERYTHING with respect to learning limits
; -- NOTE: LAC still isn't working properly!!!
;
; Revision 0.23:
; -- Added in RS232 functionality over wall control lines
;
; Revision 0.24:
; -- Touched up RS232 over wall control routine
; -- Removed 50Hz force table
; -- Added in fixes to LAC state machine
;
; Revision 0.25:
; -- Added switch set and release for wall control (NOT smart switch)
; -- into RS232 commands (Turned debouncer set and release in to subs)
; -- Added smart switch into RS232 commands (smart switch is also a sub)
; -- Re-enabled pass point test in ':' RS232 command
; -- Disabled smart switch scan when in RS232 mode
; -- Corrected relative references in debouncer subroutines
; -- RS232 'F' command still needs to be fixed
;
; Revision 0.26:
; -- Added in max. force operation until motor ramp-up is done
; -- Added in clearing of slowdown flag in set_any routine
; -- Changed RPM timeout from 30 to 60 ms
;
; Revision 0.27:
; -- Switched phase control to off, then on (was on, then off) inside
; -- each half cycle of the AC line (for noise reduction)
; -- Changed from 40ms unit max. period to 32 (will need further changes)
; -- Fixed bug in force ignore during ramp (previously jumped from down to
; -- up state machine!)
; -- Added in complete force ignore at very slow part of ramp (need to change
; -- this to ignore when very close to limit)
; -- Removed that again
; -- Bug fix -- changed force skip during ramp-up. Before, it kept counting
; -- down the force ignore timer.
;
; Revision 0.28:
; -- Modified the wall control documentation
; -- Installed blinking the wall control on an IR reversal instead of the
; -- worklight
; -- Installed blinking the wall control when a pass point is seen
;
; Revision 0.29:
; -- Changed max. RPM timeout to 100 ms
; -- Fixed wall control blink bug
; -- Raised minimum speed setting

```

NOTE: Forces still need to be set to accurate levels

Revision 0.30:

- Removed 'ei' before setting of pcon register
- Bypassed slow-down to limit during learn mode

Revision 0.31:

- Changed force ramp to a linear FORCE ramp, not a linear time ramp
- Installed a look-up table to make the ramp more linear.
- Disabled interrupts during radio pointer match
- Changed slowdown flag to a up-down-stop ramping flag

Revision 0.32:

- Changed down limit to drive lightly into floor
- Changed down limit when learning to back off of floor a few pulses

Revision 0.33:

- Changed max. speed to 2/3 when a short door is detected

Revision 0.34:

- Changed light timer to 2.5 minutes for a 50 Hz line, 4.5 minutes for a 60 Hz line. Currently, the light timer is 4.5 minutes WHEN THE UNIT FIRST POWERS UP.
- Fixed problem with leaving RP set to an extended group

Revision 0.35:

- Changed starting position of pass point counter to 0x30

Revision 0.36:

- Changed algorithm for finding down limit to cure stopping at the floor during the learn cycle
- Fixed bug in learning limits: Up limit was being updated from EEPROM during the learn cycle!
- Changed method of checking when limit is reached: calculation for distance to limit is now ALWAYS performed
- Added in skipping of limit test when position is lost

Revision 0.37:

- Revised minimum travel distance and short door constants to reflect approximately 10 RPM pulses / inch

Revision 0.38:

- Moved slowstart number closer to the limit.
- Changed backoff number from 10 to 8

Revision 0.39:

- Changed backoff number from 8 to 12

Revision 0.40:

- Changed task switcher to unburden processor
- Consolidated tasks 0 and 4
- Took extra unused code out of tasks 1, 3, 5, 7.
- Moved aux light and 4 ms timer into task 6
- Put state machine into task 2 only
- Adjusted auto_delay, motdel, rpm_time_out, force_ignore, motor_timer, obs_count for new state machine tick
- Removed force_pre prescaler (no longer needed with 4ms state machine)
- Moved updating of obs_count to one ms timer for accuracy
- Changed autoreverse delay timer into a byte-wide timer because it was only storing an 8 bit number anyways...
- Changed flash delay and light timer constants to adjust for 4ms tick

Revision 0.41

- Switched back to 4MHz operation to account for the fact that Zilog's 286733 OTP won't run at 6MHz reliably

Revision 0.42:

- Extended RPM timer so that it could measure from 0 - 524 ms with a resolution of 8us

Revision 0.43:

- Put in the new look-up table for the force pots (max RPM pulse period multiplied by 20 to scale it for the various speeds).
- Removed taskswitch because it was a redundant register
- Removed extra call to the auxlight routine
- Removed register 'temp' because, as far as I can tell, it does nothing
- Removed light_pre register
- Eliminated 'phase' register because it was never used
- Put in preliminary divide for scaling the force and speed
- Created speedlevel AND IDEAL speed registers, which are not yet used

Revision 0.47:

- Undid the work of revisions 0.44 through 0.46
- Changed ramp-up and ramp-down to an adaptive ramp system
- Changed force compare from subtract to a compare
- Removed force ignore during ramp (was a kludge)
- Changed max. RPM time out to 500 ms static
- Put WDT kick in just before main loop
- Fixed the word-wise TOEXT register
- Set default RPM to max. to fix problem of not ramping up

Revision 0.48:

- Took out adaptive ramp
- Created look-ahead speed feedback in RPM pulses

Revision 0.49:

- Removed speed feedback (again)
NOTE: Speed feedback isn't necessarily impossible, but, after all my efforts, I've concluded that the design time necessary (a large amount) isn't worth the benefit it gives, especially given the current time constraints of this project.
- Removed RPM_SET_DIFF lo and hi registers, along with IDEAL_SPEED lo and hi registers (only need them for speed feedback)
- Deleted speedlevel register (no longer needed)
- Separated the start of slowdown for the up and down directions
- Lowered the max. speed for short doors
- Set the learn button to NOT erase the memory when jogging limits

Revision 0.50:

- Fixed the force pot read to actually return a value of 0-64
- Set the max. RPM period time out to be equivalent to the force setting

Revision 0.51:

- Added in P2M_SHADOW register to make the following possible:
- Added in flashing warning light (with auto-detect)

Revision 0.52:

- Fixed the variable worklight timer to have the correct value on power-up
- Re-enabled the reason register and stackreason
- Enabled up limit to back off by one pulse if it appears to be crashing the up stop bolt.
- Set the door to ignore commands and radio when lost
- Changed start of down ramp to 220
- Changed backoff from 12 to 9
- Changed drive-past of down limit to 9 pulses

Revision 0.53:

- Fixed RS232 '9' and 'F' commands
- Implemented RS232 'K' command
- Removed 'M', 'P', and 'S' commands
- Set the learn LED to always turn off at the end of the learn limits mode

Revision 0.54:

- Reversed the direction of the pot. read to correct the direction of the min. and max. forces when dialing the pots.
- Added in "U" command (currently does nothing)

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; -- Added in "V" command to read force pot. values
;
; Revision 0.55:
; -- Changed number of pulses added in to down limit from 9 to 16
;
; Revision 0.56:
; -- Changed backoff number from 16 back to 9 (not 8!)
; -- Changed minimum force/speed from 4/20 to 10/20
;
; Revision 0.57:
; -- Changed backoff number back to 16 again
; -- Changed minimum force/speed from 10/20 back to 4/20
; -- Changed learning speed from 10/20 to 20/20
;
; Revision 0.58:
; -- Changed learning speed from 20/20 to 12/20 (same as short door)
; -- Changed force to max. during ramp-up period
; -- Changed RPM timeout to a static value of 500 ms
; -- Changed drive-past of limit from 1" to 2" of trolley travel
;   (Actually, changed the number from 10 pulses to 20 pulses)
; -- Changed start of ramp-up from 1 to 4 (i.e. the power level)
; -- Changed the algorithm when near the limit -- the door will no
;   longer avoid going toward the limit, even if it is too close
;
; Revision 0.59:
; -- Removed ramp-up bug from autoreverse of GDO
;
; Revision 0.60:
; -- Added in check for pass point counter of -1 to find position when lost
; -- Change in waking up when lost. GDO now heads toward pass point only on
;   first operation after a power outage. Heads down on all subsequent
;   operations.
; -- Created the "limits unknown" fault and prevented the GDO from traveling
;   when the limits are not set at a reasonable value
; -- Cleared the fault code on entering learn limits mode
; -- Implemented RS232 'H' command
;
; Revision 0.61:
; -- Changed limit test to look for trolley exactly at the limit position
; -- Changed search for pass point to erase limit memory
; -- Changed setup position to 2" above the pass point
; -- Set the learn LED to turn off whenever the L_A_C is cleared
; -- Set the learn limits mode to shut off whenever the worklight times out
;
; Revision 0.62:
; -- Removed test for being exactly at down limit (it disabled the drive into
;   the limit feature)
; -- Fixed bug causing the GDO to ignore force when it should autoreverse
; -- Added in ignoring commands when lost and traveling up
;
; Revision 0.63:
; -- Installed MinSpeed register to vary minimum speed with force pot
;   setting
; -- Created main loop routine to scale the min speed based on force pot.
; -- Changed drive-past of down limit from 20 to 30 pulses (2" to 3")
;
; Revision 0.64:
; -- Changed learning algorithm to utilize block. (Changed autoreverse to
;   add in 1/2" to position instead of backing the trolley off of the floor)
; -- Enabled ramp-down when nearing the up limit in learn mode
;
; Revision 0.65:
; -- Put special case in speed check to enable slow down near the up limit
;
; Revision 0.66:
; -- Changed ramp-up: Ramping up of speed is now constant -- the ramp-down
;   is the only ramp affected by the force pot. setting
; -- Changed ramp-up and ramp-down tests to ensure that the GDO will get UP
;   to the minimum speed when we are inside the ramp-down zone (The above

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;      change necessitated this)
;      -- Changed down limit to add in 0.2" instead f 0.5"
;
; Revision 0.67:
;      -- Removed minimum travel test in set_arev_state
;      -- Moved minimum distance of down limit from pass point from 5" to 2"
;      -- Disabled moving pass point when only one pass point has been seen
;
; Revision 0.68:
;      -- Set error in learn state if no pass point is seen
;
; Revision 0.69:
;      -- Added in decrement of pass point counter in learn mode to kill bugs
;      -- Fixed bug: Force pots were being ignored in the learn mode
;      -- Added in filtering of the RPM (RPM_FILTER register and a routine in
;         the one ms timer)
;      -- Added in check of RPM filter inside RPM interrupt
;      -- Added in polling RPM pin inside RPM interrupt
;      -- Re-enabled stopping when in learn mode and position is lost
;
; Revision 0.70:
;      -- Removed old method of filtering RPM
;      -- Added in a "debouncer" to filter the RPM
;
; Revision 0.71:
;      -- Changed "debouncer" to automatically vector low whenever an RPM pulse
;         is considered valid
;
; Revision 0.72:
;      -- Changed number of pulses added in to down limit to 0. Since the actual
;         down limit test checks for the position to be BEYOND the down limit
;         this is the equivalent of adding one pulse into the down limit
;
; Revision 0.74:
;      -- Undid the work of rev. 0.73
;      -- Changed number of pulses added in to down limit to 1. Noting the comment
;         in rev. 0.72, this means that we are adding in 2 pulses
;      -- Changed learning speed to vary between 8/20 and 12/20, depending upon
;         the force pot. setting
;
; Revision 0.75:
;      -- Installed power-up chip ID on P22, P23, P24, and P25
;         Note: ID is on P24, P23, and P22. P25 is a strobe to signal valid data
;         First chip ID is 001 (with strobe, it's 1001)
;      -- Changed set_any routine to re-enable the wall control just in case we
;         stopped while the wall control was being turned off (to avoid disabling
;         the wall control completely)
;      -- Changed speed during learn mode to be 2/3 speed for first seven seconds,
;         then to slow down to the minimum speed to make the limit learning the same
;         as operation during normal travel.
;
; Revision 0.76:
;      -- Restored learning to operate only at 60% speed
;
; Revision 0.77:
;      -- Set unit to reverse off of floor and subtract 1" of travel
;      -- Reverted to learning at 40% - 60% of full speed
;
; Revision 0.78:
;      -- Changed rampflag to have a constant for running at full speed
;      -- Us d the above change to simplify the force ignore routine
;      -- Also used it to change the RPM time out. The time out is now set equal
;         to the pot setting, except during the ramp up when it is set to 500 ms.
;      -- Changed highest force pot setting to be exactly equal to 500ms.
;
; Revision 0.79:
;      -- Changed setup routine to reverse off block (y t again). Added in one pulse.
;
; Revision 1.0:

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; -- Enabled RS232 version number return
; -- Enabled ROM checksum. Cleaned up documentation
;
; Revision 1.1:
; -- Tweaked light times for 8.192 ms prescale instead of 8.0 ms prescale
; -- Changed compare statement inside setvarlight to 'uge' for consistency
; -- Changed one-shot low time to 2 ms for power line
; -- Changed one-shot low time to truly count falling-edge-to-falling-edge
;
; Revision 1.2:
; -- Eliminated testing for lost GDO in set_up_dir_state (is already taken
;   care of by set_dn_dir_state)
; -- Created special time for max. run motor timer in learn mode: 50 seconds
;
; Revision 1.3:
; -- Fixed bug in set_any to fix stack imbalance
; -- Changed short door discrimination point to 78"
;
; Revision 1.4:
; -- Changed second 'di' to 'ei' in KnowSimCode
; -- Changed IR protector to ignore for first 0.5 second of travel
; -- Changed blinking time constant to take it back to 2 seconds before travel
; -- Changed blinking code to ALWAYS flash during travel, with pre-travel flash
;   when module is properly detected
; -- Put in bounds checking on pass point counter to keep it in line
; -- Changed driving into down limit to consider the system lost if floor not seen
;
; Revision 1.5:
; -- Changed blinking of wall control at pass point to be a one-shot timer
;   to correct problems with bad passpoint connections and stopping at pass
;   point to cause wall control ignore.
;
; Revision 1.6:
; -- Fixed blinking of wall control when indicating IR protector reversal
;   to give the blink a true 50% duty cycle.
; -- Changed blinker output to output a constant high instead of pulsing.
; -- Changed P2S_POR to 1010 (Indicate Siminor unit)
;
; Revision 1.7:
; -- Disabled Siminor Radio
; -- Changed P2S_POR to 1011 (Indicate Lift-Master unit)
; -- Added in one more conditional assembly point to avoid use of simradio label
;
; Revision 1.8:
; -- Re-enabled Siminor Radio
; -- Changed P2S_POR back to 1010 (Siminor)
; -- Re-fixed blinking of wall control LED for protector reversal
; -- Changed blinking of wall control LED for indicating pass point
; -- Fixed error in calculating highest pass point value
; -- Fixed error in calculating lowest pass point value
;
; Revision 1.9:
; -- Lengthened blink time for indicating pass point
; -- Installed a max. travel distance when lost
;   -- Removed skipping up limit test when lost
;   -- Reset the position when lost and force reversing
; -- Installed sample of pass point signal when changing states
;
; Revision 2.0:
; -- Moved main loop test for max. travel distance (was causing a memory
;   fault before)
;
; Revision 2.1:
; -- Changed limit test to use 11000000b instead of 10000000b to ensure
;   only setting up limit when we're actually close.
;
; Revision 2.2:
; -- Changed minimum speed scaling to move it further down the pot. rotation.
;   Formula is now: ((force - 24) / 4) + 4, truncated to 12

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; -- Changed max. travel test to be inside motor state machine. Max. travel
; test calculates for limit position differently when the system is lost.
; -- Rev rted limit test to use 10000000b
; -- Changed some jp's to jr's to conserve code space
; -- Changed loading of reason byte with 0 to clearing of reason byte (very
; desperate for space)
;
Revision 2.3:
; -- Disabled Siminor Radio
; -- Changed P2S_POR to 1011 (Lift-Master)
;
Revision 2.4:
; -- Re-enabled Siminor Radio
; -- Changed P2S_POR to 1010 (Siminor)
; -- Changed wall control LED to also flash during learn mode
; -- Changed reaction to single pass point near floor. If only one pass point
; is seen during the learn cycle, and it is too close to the floor, the
; learn cycle will now fail.
; -- Removed an ei from the pass point when learning to avoid a race condition
;
Revision 2.5:
; -- Changed backing off of up limit to only occur during learn cycle. Backs
; off by 1/2" if learn cycle force stops within 1/2" of stop bolt.
; -- Removed considering system lost if floor not seen.
; -- Changed drive-past of down limit to 36 pulses (3")
; -- Added in clearing of power level whenever motor gets stopped (to turn off
; the FET's sooner)
; -- Added in a 40ms delay (using the same MOTDEL register as for the traveling
; states) to delay the shut-off of the motor relay. This should enable the
; motor to discharge some energy before the relay has to break the current
; flow)
; -- Created STOPNOFLASH label -- it looks like it should have been there all along
; -- Moved incrementing MOTDEL timer into head of state machine to conserve space
;
Revision 2.6:
; -- Fixed back-off of up limit to back off in the proper direction
; -- Added in testing for actual stop state in back-off (before was always backing
; off the limit)
; -- Simplified testing for light being on in 'set any' routine; eliminated lights
; register
;
Revision 2.7: (Test-only revision)
; -- Moved ei when testing for down limit
; -- Eliminated testing for negative number in radio time calculation
; -- Installed a primitive debouncer for the pass point (out of paranoia)
; -- Changed a pass point in the down direction to correspond to a position of 1
; -- Installed a temporary echo of the RPM signal on the blinker pin
; -- Temporarily disabled ROM checksum
; -- Moved three subroutines before address 0101 to save space (2.7B)
; -- Framed look up using upforce and dnforce registers with di and ei to
; prevent corruption of upforce or dnforce while doing math (2.7C)
; -- Fixed error in definition of pot_count register (2.7C)
; -- Disabled actual number check of RPM perpod for debug (2.7D)
; -- Added in di at test_up_sw and test_dn_sw for ramping up period(2.7D)
; -- Set RPM_TIME_OUT to always be loaded to max value for debug (2.7E)
; -- Set RPM_TIME_OUT to round up by two instead of one (2.7F)
; -- Removed 2.7E revision (2.7F)
; -- Fixed RPM_TIME_OUT to round up in both the up and down direction(2.7G)
; -- Installed constant RS232 output of RPM_TIME_OUT register (2.7H)
; -- Enabled RS232 'U' and 'V' commands (2.7I)
; -- Disabled constant output of 2.7H (2.7I)
; -- Set RS232 'U' to output RPM_TIME_OUT(2.7I)
; -- Removed disable of actual RPM number check (2.7J)
; -- Removed pulsing to indicate RPM interrupt (2.7J)
; -- 2.7J note -- need to remove 'u' command function
;
Revision 2.8:
; -- Removed interrupt enable before resetting rpm_time_out. This will introduce
; roughly 30us of extra delay in time measurement, but should take care of

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;
;      10 = OPEN/CLOSE/STOP
; 27      unused      Fixed / roll
;                               Upper word = fixed/roll byte
;                               Lower word = unused
;
; 28      CYCLE COUNTER 1ST 16 BITS
; 29      CYCLE COUNTER 2ND 16 BITS
; 2A      VACATION FLAG
;
;      Vacation Flag , Last Operation
;      0000      XXXX in vacation
;      1111      XXXX out of vacation
;
; 2B      A MEMORY ADDRESS LAST WRITTEN
; 2C      IRLIGHTADDR 4-22-97
; 2D      Up Limit
; 2E      Pass point counter / Last operating state
; 2F      Down Limit
;
; 30-3F Force Back trace

```

RS232 DATA

REASON

```

00      COMMAND
10      RADIO COMMAND
20      FORCE
30      AUX OBS
40      A REVERSE DELAY
50      LIMIT
60      EARLY LIMIT
70      MOTOR MAX TIME, TIME OUT
80      MOTOR COMMANDED OFF RPM CAUSING AREV
90      DOWN LIMIT WITH COMMAND HELD
A0      DOWN LIMIT WITH THE RADIO HELD
B0      RELEASE OF COMMAND OR RADIO AFTER A FORCED
UP MOTOR ON DUE TO RPM PULSE WITHG MOTOR OFF

```

STATE

```

00      AUTOREVERSE DELAY
01      TRAVELING UP DIRECTION
02      AT THE UP LIMIT AND STOPPED
03      ERROR RESET
04      TRAVELING DOWN DIRECTION
05      AT THE DOWN LIMIT
06      STOPPED IN MID TRAVEL

```

DIAG

```

1) AOBs SHORTED
2) AOBs OPEN / MISS ALIGNED
3) COMMAND SHORTED
4) PROTECTOR INTERMITTENT
5) CALL DEALER
   NO RPM IN THE FIRST SECOND
6) RPM FORCED A REVERSE
7) LIMITS NOT LEARNED YET

```

DOG 2

```
; DOG 2 IS A SECONDARY WATCHDOG USED TO
; RESET THE SYSTEM IF THE LOWEST LEVEL "MAINLOOP"
; IS NOT REACHED WITHIN A 3 SECOND
```

```
;-----
; Conditional Assembly
;-----
```

```
GLOBALs ON ; Enable a symbol file
Yes .equ 1
No .equ 0
TwoThirtyThree .equ Yes
UseSiminor .equ Yes
```

```
;-----
; EQUATE STATEMENTS
;-----
```

```
check_sum_value .equ 065H ; CRC checksum for ROM code
TIMER_1_EN .equ 0CH ; TMR mask to start timer 1

MOTORTIME .equ (27000 / 4) ; Max. run for motor = 27 sec (4 ms tick)
LTIME .equ (500 / 4) ; Delay before learning limits is 0.5 seconds
LEARNTIME .equ (50000 / 4) ; Max. run for motor in learn mode

PWM_CHARGE .equ 00H ; PWM state for old force pots.
LIGHT .equ OFFH ; Flag for light on constantly
LIGHT_ON .equ 10000000B ; P0 pin turning on worklight
MOTOR_UP .equ 01000000B ; P0 pin turning on the up motor
MOTOR_DN .equ 00100000B ; P0 pin turning on the down motor

UP_OUT .equ 00010000B ; P3 pin output for up force pot.
DOWN_OUT .equ 00100000B ; P3 pin output for down force pot.
DOWN_COMP .equ 00000001B ; P0 pin input for down force pot.
UP_COMP .equ 00000010B ; P0 pin input for up force pot.

FALSEIR .equ 00000001B ; P2 pin for false AOBS output
LINEINPIN .equ 00010000B ; P2 pin for reading in AC line

PPointPort .equ p2 ; Port for pass point input
PassPoint .equ 00001000B ; Bit mask for pass point input

PhasePrt .equ p0 ; Port for phase control output
PhaseHigh .equ 00010000B ; Pin for controlling FET's

CHARGE_SW .equ 10000000B ; P3 Pin for charging the wall control
DIS_SW .equ 01000000B ; P3 Pin for discharging the wall control
SWITCHES1 .equ 00001000B ; P0 Pin for first wall control input
SWITCHES2 .equ 00000100B ; P0 Pin for second wall control input

P01M_INIT .equ 00000101B ; set mode p00-p03 in p04-p07 out
P2M_INIT .equ 01011100B ; P2M initialization for operation
P2M_POR .equ 01000000B ; P2M initialization for output of chip ID
P3M_INIT .equ 00000011B ; set port3 p30-p33 input ANALOG mode

P01S_INIT .equ 10000000B ; Set init. state as worklight on, motor off
P2S_INIT .equ 00000110B ; Init p2 to have LED off
P2S_POR .equ 00101010B ; P2 init to output a chip ID (P25, P24, P23, P22)
P3S_INIT .equ 00000000B ; Init p3 to have everything off

BLINK_PIN .equ 00000100B ; Pin which controls flasher module

P2M_ALLOUTS .equ 01011100B ; Pins which need to be refreshed to outputs
P2M_ALLINS .equ 01011000B ; Pins which need to be refreshed to inputs

RsPerHalf .equ 104 ; RS232 period 1200 Baud half time 416uS
```

```

RsPerFull      .equ 208      ; RS232 period full time 832us
RsPer1P22     .equ 00      ; RS232 period 1.22 unit times 1.024ms (00 = 256)

FLASH         .equ OFFH      ;
WORKLIGHT     .equ LIGHT_ON  ; Pin for toggling state of worklight

PPOINTPULSES .equ 897      ; Number of RPM pulses between pass points

SetupPos      .equ (65535 - 20) ; Setup position -- 2" above pass point

CMD_TEST      .equ 00      ; States for old wall control routine
WL_TEST       .equ 01
VAC_TEST      .equ 02
CHARGE        .equ 03
RSSTATUS      .equ 04      ; Hold wall control ckt. in RS232 mode
WALLOFF       .equ 05      ; Turn off wall control LED for blinks

AUTO_REV      .equ 00H      ; States for GDO state machine
UP_DIRECTION  .equ 01H
UP_POSITION   .equ 02H
DN_DIRECTION  .equ 04H
DN_POSITION   .equ 05H
STOP          .equ 06H
CMD_SW        .equ 01H      ; Flags for switches hit
LIGHT_SW      .equ 02H
VAC_SW        .equ 04H

TRUE          .equ OFFH      ; Generic constants
FALSE         .equ 00H

FIXED_MODE    .equ 10101010b ;Fixed mode radio
ROLL_MODE     .equ 01010101b ;Rolling mode radio
FIXED_TEST    .equ 00000000b ;Unsure of mode -- test fixed
ROLL_TEST     .equ 00000001b ;Unsure of mode -- test roll
FIXED_MASK    .equ FIXED_TEST ;Bit mask for fixed mode
ROLL_MASK     .equ ROLL_TEST  ;Bit mask for rolling mode

FIXTHR       .equ 03H      ;Fixed code decision threshold
DTHR         .equ 02H      ;Rolling code decision threshold
FIXSYNC       .equ 08H      ;Fixed code sync threshold
DSYNC        .equ 04H      ;Rolling code sync threshold
FIXBITS       .equ 11      ;Fixed code number of bits
DBITS        .equ 21      ;Rolling code number of bits

EQUAL        .equ 00      ;Counter compare result constants
BACKWIN      .equ 7FH      ;
FWDWIN       .equ 80H      ;
OUTOFWIN     .equ OFFH      ;

AddressCounter .equ 27H
AddressAPointer .equ 2BH

CYCCOUNT     .equ 28H

TOUCHID      .equ 21H      ;Touch code ID
TOUCHROLL    .equ 22H      ;Touch code roll value
TOUCHPERM     .equ 20H      ;Touch code permanent password
TOUCHTEMP     .equ 24H      ;Touch code temporary password
DURAT        .equ 25H      ;Touch code temp. duration

VERSIONNUM    .equ 088H      ;Version: PRO7000 V2.8
;4-22-97
IRLIGHTADDR  .EQU 2CH      ;work light feature on or off
DISABLED     .EQU 00H      ;00 = disabled, FF = enabled
;
RTYPEADDR    .equ 26H      ;Radio transmitter type
VACATIONADDR .equ 2AH
MODEADDR     .equ 27H      ;Rolling/Fixed mode in EEPROM
;High byte = don't care (now)

```

```

;Low byte = RadioMode flag
UPLIMADDR .equ 2DH ;Addr ss of up limit
LASTSTATEADDR .equ 2EH ;Address of last state
DNLIMADDR .equ 2FH ;Address of down limit

NOEECOMM .equ 01111111b ;Flag: skip radio read/write
NOINT .equ 10000000b ;Flag: skip radio interrupts

RDROPTIME .equ 125 ;Radio drop-out time: 0.5s

LRNOCS .equ 0AAH ;Learn open/close/stop
BRECEIVED .equ 077H ;B code received flag
LRNLIGHT .equ 0BBH ;Light command trans.
LRNTEMP .equ 0CCH ;Learn touchcode temporary
LRNDURTN .equ 0DDH ;Learn t.c. temp. duration
REGLEARN .equ 0EEH ;Regular learn mode
NORMAL .equ 00H ;Normal command trans.

ENTER .equ 00H ;Touch code ENTER key
POUND .equ 01H ;Touch code # key
STAR .equ 02H ;Touch code * key

ACTIVATIONS .equ 0AAH ;Number of activations mode
HOURS .equ 055H ;Number of hours mode

;Flags for Ramp Flag Register
STILL .equ 00H ; Motor not moving
RAMPUP .equ 0AAH ; Ramp speed up to maximum
RAMPDOWN .equ 0FFH ; Slow down the motor to minimum
FULLSPEED .equ 0CCH ; Running at full speed

UPSLOWSTART .equ 200 ; Distance (in pulses) from limit when slow-
down
DNSLOWSTART .equ 220 ; of GDO motor starts (for up and down
direction)

BACKOFF .equ 16 ; Distance (in pulses) to back trolley off of
floor ; when learning limits by reversing off of
floor

SHORTDOOR .equ 936 ; Travel distance (in pulses) that
discriminates a ; one piece door (slow travel) from a normal
door ; (normal travel) (Roughly 78")

;-----
; PERIODS
;-----

AUTO_REV_TIME .equ 124 ; (4 ms prescale)
MIN_COUNT .equ 02H ; pwm start point
TOTAL_PWM_COUNT .equ 03FH ; pwm end = start + 2*total-1
FLASH_TIME .equ 61 ; 0.25 sec flash time

;4.5 MINUTE USA LIGHT TIMER

USA_LIGHT_HI .equ 080H ; 4.5 MIN
USA_LIGHT_LO .equ 0BEH ; 4.5 MIN

;2.5 MINUTE EUROPEAN LIGHT TIMER

EURO_LIGHT_HI .equ 047H ; 2.5 MIN
EURO_LIGHT_LO .equ 086H ; 2.5 MIN

ONE_SEC .equ 0F4H ; WITH A /4 IN FRONT

```

```

CMD_MAKE                .equ    8                ; cycle count *10mS
CMD_BREAK               .equ    (255-8)
LIGHT_MAKE              .equ    8                ; cycle count *11mS
LIGHT_BREAK             .equ    (255-8)
VAC_MAKE_OUT            .equ    4                ; cycle count *100mS
VAC_BREAK_OUT           .equ    (255-4)
VAC_MAKE_IN             .equ    2
VAC_BREAK_IN            .equ    (255-2)

VAC_DEL                 .equ    8                ; Delay 16 ms for vacation
CMD_DEL_EX              .equ    6                ; Delay 12 ms ( 5*2 + 2)
VAC_DEL_EX              .equ    50               ; Delay 100 ms

```

```

;*****
;      PREDEFINED REG
;*****

```

```

ALL_ON_IMR              .equ    00111101b        ; turn on int for timers rpm auxobs radio
RETURN_IMR              .equ    00111100b        ; return on the IMR

RadioImr                .equ    00000001b        ; turn on the radio only

```

```

-----
;      GLOBAL REGISTERS
-----

```

```

STATUS                  .equ    04H              ; CMD_TEST 00
                                           ; WL_TEST 01
                                           ; VAC_TEST 02
                                           ; CHARGE 03

STATE                   .equ    05H              ; state register
LineCtr                 .equ    06H              ;
RampFlag                .equ    07H              ; Ramp up, ramp down, or stop
AUTO_DELAY              .equ    08H
LinePer                 .equ    09H              ; Period of AC line coming in
MOTOR_TIMER_HI          .equ    0AH
MOTOR_TIMER_LO          .equ    0BH
MOTOR_TIMER             .equ    0AH
LIGHT_TIMER_HI          .equ    0CH
LIGHT_TIMER_LO          .equ    0DH
LIGHT_TIMER             .equ    0CH
AOBSF                   .equ    0EH
PrevPass                .equ    0FH

CHECK_GRP               .equ    10H
check_sum               .equ    r0                ; check sum pointer
rom_data                .equ    r1
test_adr_hi             .equ    r2
test_adr_lo             .equ    r3
test_adr                .equ    rr2
CHECK_SUM               .equ    CHECK_GRP+0        ; check sum reg for por
ROM_DATA                .equ    CHECK_GRP+1        ; data read
LIM_TEST_HI             .equ    CHECK_GRP+0        ; Compare registers for measuring
LIM_TEST_LO             .equ    CHECK_GRP+1        ; distance to limit
LIM_TEST                .equ    CHECK_GRP+0        ;
AUXLEARNSW             .equ    CHECK_GRP+2        ;
RRT0                    .equ    CHECK_GRP+3        ;
RPM_ACOUNT            .equ    CHECK_GRP+4        ; to test for active rpm
RS_COUNTER              .equ    CHECK_GRP+5        ; rs232 byte counter
RS232DAT                .equ    CHECK_GRP+6        ; rs232 data

RADIO_CMD               .equ    CHECK_GRP+7        ; radio command
R_DEAD_TIME            .equ    CHECK_GRP+8        ;
FAULT                  .equ    CHECK_GRP+9        ;
VACFLAG                .equ    CHECK_GRP+10       ; VACATION mode flag
VACFLASH               .equ    CHECK_GRP+11

```



```
VACCHANGE      .equ  CHECK_GRP+12
FAULTTIME      .equ  CHECK_GRP+13
FORCE_IGNORE   .equ  CHECK_GRP+14
FAULTCODE      .equ  CHECK_GRP+15
```

```
TIMER_GROUP    .equ  20H
position_hi     .equ  r0
position_lo     .equ  r1
position        .equ  rr0
up_limit_hi     .equ  r2
up_limit_lo     .equ  r3
up_limit        .equ  rr2
switch_delay    .equ  r4
obs_count       .equ  r6
rscommand       .equ  r9
rs_temp_hi      .equ  r10
rs_temp_lo      .equ  r11
rs_temp         .equ  rr10
```

```
POSITION_HI     .equ  TIMER_GROUP+0
POSITION_LO     .equ  TIMER_GROUP+1
POSITION        .equ  TIMER_GROUP+0
UP_LIMIT_HI     .equ  TIMER_GROUP+2
UP_LIMIT_LO     .equ  TIMER_GROUP+3
UP_LIMIT        .equ  TIMER_GROUP+2
SWITCH_DELAY    .equ  TIMER_GROUP+4
OnePass         .equ  TIMER_GROUP+5
OBS_COUNT       .equ  TIMER_GROUP+6
RsMode          .equ  TIMER_GROUP+7
Divisor         .equ  TIMER_GROUP+8
RSCOMMAND       .equ  TIMER_GROUP+9
RS_TEMP_HI      .equ  TIMER_GROUP+10
RS_TEMP_LO      .equ  TIMER_GROUP+11
RS_TEMP         .equ  TIMER_GROUP+10
PowerLevel      .equ  TIMER_GROUP+12
PhaseTMR        .equ  TIMER_GROUP+13
PhaseTime       .equ  TIMER_GROUP+14
MaxSpeed        .equ  TIMER_GROUP+15
```

```
; Number to divide by
```

```
; Current step in 20-step phase ramp-up
; Timer for turning on and off phase control
; Current time reload value for phase timer
; Maximum speed for this kind of door
```

```
; *****
; LEARN EE GROUP FOR LOOPS ECT
; *****
```

```
LEARNEE_GRP     .equ  30H
TEMPH           .equ  LEARNEE_GRP
TEMPL           .equ  LEARNEE_GRP+1
P2M_SHADOW      .equ  LEARNEE_GRP+2
LEARNDDB        .equ  LEARNEE_GRP+3
LEARNT          .equ  LEARNEE_GRP+4
ERASET          .equ  LEARNEE_GRP+5
MTEMPH          .equ  LEARNEE_GRP+6
MTEMPL          .equ  LEARNEE_GRP+7
MTEMP           .equ  LEARNEE_GRP+8
SERIAL           .equ  LEARNEE_GRP+9
ADDRESS         .equ  LEARNEE_GRP+10
ZZWIN           .equ  LEARNEE_GRP+11
T0_OFLOW        .equ  LEARNEE_GRP+12
T0EXT           .equ  LEARNEE_GRP+13
T0EXTWORD       .equ  LEARNEE_GRP+12
T125MS          .equ  LEARNEE_GRP+14
SKIPRADIO       .equ  LEARNEE_GRP+15
```

```
; Readable shadow of P2M register
; learn debouncer
; learn timer
; erase timer
; memory temp
; memory temp
; memory temp
; data to & from nonvol memory
; address for the serial nonvol memory
; radio 00 code window
; Third byte of T0 counter
; t0 extend dec'd every T0 int
; Word-wide T0 extension
; 125mS counter
; flag to skip radio read, write if
; learn or vacation talking to it
```

```
temph           .equ  r0
templ           .equ  r1
learndb         .equ  r3
learnt          .equ  r4
eraset          .equ  r5
mtemp           .equ  r6
; learn debouncer
; learn timer
; erase timer
; memory temp
```

```

mtempl      .equ    r7          ; memory temp
mtemp       .equ    r8          ; memory temp
serial      .equ    r9          ; data to and from nonvol mem
address     .equ    r10         ; addr for serial nonvol memory
zzwin       .equ    r11
t0_oflow    .equ    r12         ; Overflow counter for T0
t0ext       .equ    r13         ; t0 extend dec'd every T0 int
t0extword   .equ    rr12        ; Word-wide T0 extension
tl25ms      .equ    r14         ; 125mS counter
skipradio   .equ    r15         ; flag to skip radio read, write if
                                   ; learn or vacation talking to it

```

```

FORCE_GROUP .equ    40H
dnforce     .equ    r0
upforce     .equ    r1
loopreg     .equ    r3
up_force_hi .equ    r4
up_force_lo .equ    r5
up_force    .equ    rr4
dn_force_hi .equ    r6
dn_force_lo .equ    r7
dn_force    .equ    rr6
force_add_hi .equ    r8
force_add_lo .equ    r9
force_add   .equ    rr8
up_temp     .equ    r10
dn_temp     .equ    r11
pot_count   .equ    r12
force_temp_of .equ    r13
force_temp_hi .equ    r14
force_temp_lo .equ    r15

```

```

DNEFORCE    .equ    40H
UPFORCE     .equ    41H
AOBTEST     .equ    42H
LoopReg     .equ    43H
UP_FORCE_HI .equ    44H
UP_FORCE_LO .equ    45H
DN_FORCE_HI .equ    46H
DN_FORCE_LO .equ    47H
UP_TEMP     .equ    4AH
DN_TEMP     .equ    4BH
POT_COUNT   .equ    4CH
FORCE_TEMP_OF .equ    4CH
FORCE_TEMP_HI .equ    4EH
FORCE_TEMP_LO .equ    4FH

```

```

RPM_GROUP   .equ    50H

rtypes2     .equ    r0
stackflag   .equ    r1
rpm_temp_of .equ    r2
rpm_temp_hi .equ    r3
rpm_temp_hiword .equ    rr2
rpm_temp_lo .equ    r4
rpm_past_hi .equ    r5
rpm_past_lo .equ    r6
rpm_period_hi .equ    r7
rpm_period_lo .equ    r8
divcounter  .equ    r11
rpm_count   .equ    r12
rpm_time_out .equ    r13

```

```

RTypes2     .equ    RPM_GROUP+0
STACKFLAG   .equ    RPM_GROUP+1

```

```

; Counter for dividing RPM time

```

```

RPM_TEMP_OF      .equ    RPM_GROUP+2                ; Overflow for RPM Time
RPM_TEMP_HI     .equ    RPM_GROUP+3                ;
RPM_TEMP_HWORD  .equ    RPM_GROUP+2                ; High word of RPM Time
RPM_TEMP_LO     .equ    RPM_GROUP+4
RPM_PAST_HI     .equ    RPM_GROUP+5
RPM_PAST_LO     .equ    RPM_GROUP+6
RPM_PERIOD_HI   .equ    RPM_GROUP+7
RPM_PERIOD_LO   .equ    RPM_GROUP+8
DN_LIMIT_HI     .equ    RPM_GROUP+9                ;
DN_LIMIT_LO     .equ    RPM_GROUP+10               ;
DIVCOUNTER      .equ    RPM_GROUP+11               ; Counter for dividing RPM time
RPM_FILTER      .equ    RPM_GROUP+11               ; DOUBLE MAPPED register for filtering signal
RPM_COUNT       .equ    RPM_GROUP+12
RPM_TIME_OUT    .equ    RPM_GROUP+13
BLINK_HI        .equ    RPM_GROUP+14               ; Blink timer for flashing the
BLINK_LO        .equ    RPM_GROUP+15               ; about-to-travel warning light
BLINK           .equ    RPM_GROUP+14               ; Word-wise blink timer

```

```

; *****
; RADIO GROUP
; *****
RadioGroup      .equ    60H                ;
RTemp           .equ    RadioGroup          ; radio temp storage
RTempH          .equ    RadioGroup+1        ; radio temp storage high
RTempL          .equ    RadioGroup+2        ; radio temp storage low
RTimeAH         .equ    RadioGroup+3        ; radio active time high byte
RTimeAL         .equ    RadioGroup+4        ; radio active time low byte
RTimeIH         .equ    RadioGroup+5        ; radio inactive time high byte
RTimeIL         .equ    RadioGroup+6        ; radio inactive time low byte
Radio1H         .equ    RadioGroup+7        ; sync 1 code storage
Radio1L         .equ    RadioGroup+8        ; sync 1 code storage
RadioC          .equ    RadioGroup+9        ; radio word count
PointerH        .equ    RadioGroup+10       ;
PointerL        .equ    RadioGroup+11       ;
AddValueH       .equ    RadioGroup+12       ;
AddValueL       .equ    RadioGroup+13       ;
Radio3H         .equ    RadioGroup+14        ; sync 3 code storage
Radio3L         .equ    RadioGroup+15        ; sync 3 code storage
rtemp           .equ    r0                  ; radio temp storage
rtempH          .equ    r1                  ; radio temp storage high
rtempL          .equ    r2                  ; radio temp storage low
rtimeah         .equ    r3                  ; radio active time high byte
rtimeal         .equ    r4                  ; radio active time low byte
rtimeih         .equ    r5                  ; radio inactive time high byte
rtimeil         .equ    r6                  ; radio inactive time low byte
radio1h         .equ    r7                  ; sync 1 code storage
radio1l         .equ    r8                  ; sync 1 code storage
radioc          .equ    r9                  ; radio word count
pointerh        .equ    r10                 ;
pointerl        .equ    r11                 ;
pointer         .equ    rr10                ; Overall pointer for ROM
addvalueh       .equ    r12                 ;
addvaluell      .equ    r13                 ;
radio3h         .equ    r14                 ; sync 3 code storage
radio3l         .equ    r15                 ; sync 3 code storage
w2              .equ    rr14                ; For Siminor revision

```

```

CounterGroup    .equ    070h                ; counter group
TestReg         .equ    CounterGroup        ; Test area when dividing
BitMask         .equ    CounterGroup+01     ; Mask for transmitters
LastMatch       .equ    CounterGroup+02     ; last matching code address
LoopCount       .equ    CounterGroup+03     ; loop counter
CounterA        .equ    CounterGroup+04     ; counter translation MSB
CounterB        .equ    CounterGroup+05     ;
CounterC        .equ    CounterGroup+06     ;

```

```

CounterD      .equ    CounterGroup+07      ; counter translation LSB
MirrorA       .equ    CounterGroup+08      ; back translation MSB
MirrorB       .equ    CounterGroup+09      ;
MirrorC       .equ    CounterGroup+010     ;
MirrorD       .equ    CounterGroup+011     ; back translation LSB
COUNT1H     .equ    CounterGroup+012     ; received count
COUNT1L     .equ    CounterGroup+013
COUNT3H     .equ    CounterGroup+014
COUNT3L     .equ    CounterGroup+015

loopcount     .equ    r3
countera     .equ    r4
counterb     .equ    r5
counterc     .equ    r6
counterd     .equ    r7
mirrora      .equ    r8
mirrorb      .equ    r9
mirrorc      .equ    r10
mirrord      .equ    r11

Radio2Group   .equ    080H

PREVFIX       .equ    Radio2Group + 0
PREVTMP       .equ    Radio2Group + 1
ROLLBIT       .equ    Radio2Group + 2
RTimeDH       .equ    Radio2Group + 3
RTimeDL       .equ    Radio2Group + 4
RTimePH       .equ    Radio2Group + 5
RTimePL       .equ    Radio2Group + 6
ID_B          .equ    Radio2Group + 7
SW_B          .equ    Radio2Group + 8
RADIOBIT      .equ    Radio2Group + 9
RadioTimeOut  .equ    Radio2Group + 10
RadioMode     .equ    Radio2Group + 11      ;Fixed or rolling mode
BitThresh     .equ    Radio2Group + 12      ;Bit decision threshold
SyncThresh    .equ    Radio2Group + 13      ;Sync pulse decision threshold
MaxBits       .equ    Radio2Group + 14      ;Maximum number of bits
RFlag         .equ    Radio2Group + 15      ;Radio flags

prevfix       .equ    r0
prevtmp       .equ    r1
rollbit       .equ    r2
id_b          .equ    r7
sw_b          .equ    r8
radiobit      .equ    r9
radiotimeout  .equ    r10
radiomode     .equ    r11
rflag         .equ    r15

OriginalGroup .equ    90H
SW_DATA       .equ    OriginalGroup+0
ONEP2         .equ    OriginalGroup+1      ; 1.2 SEC TIMER TICK .125
LAST_CMD      .equ    OriginalGroup+2      ; LAST COMMAND FROM
                                           ; = 55 WALL CONTROL
                                           ; = 00 RADIO
CodeFlag      .equ    OriginalGroup+3      ; Radio code type flag
                                           ; FF = Learning open/close/stop
                                           ; 77 = b code
                                           ; AA = open/close/stop code
                                           ; 55 = Light control transmitter
                                           ; 00 = Command or unknown
RPMONES       .equ    OriginalGroup+4      ; RPM Pulse One Sec. Disable
RPMCLEAR      .equ    OriginalGroup+5      ; RPM PULSE CLEAR & TEST TIMER
FAREVFLAG     .equ    OriginalGroup+6      ; RPM FORCED AREV FLAG
                                           ; 88H FOR A FORCED REVERSE

FLASH_FLAG    .equ    OriginalGroup+7
FLASH_DELAY   .equ    OriginalGroup+8

```

```

REASON .equ OriginalGroup+9
FLASH_COUNTER .equ OriginalGroup+10
RadioTypes .equ OriginalGroup+11 ; Types for one page of tx's
LIGHT_FLAG .equ OriginalGroup+12
CMD_DEB .equ OriginalGroup+13
LIGHT_DEB .equ OriginalGroup+14
VAC_DEB .equ OriginalGroup+15

NextGroup .equ 0A0H
SDISABLE .equ NextGroup+0 ; system disable timer
PRADIO3H .equ NextGroup+1 ; 3 mS code storage high byte
PRADIO3L .equ NextGroup+2 ; 3 mS code storage low byte
PRADIO1H .equ NextGroup+3 ; 1 mS code storage high byte
PRADIO1L .equ NextGroup+4 ; 1 mS code storage low byte
RTO .equ NextGroup+5 ; radio time out
;RFlag .equ NextGroup+6 ; radio flags
EnableWorkLight .equ NextGroup+6 ; 4-22-97 work light function on or off?
RINFILTER .equ NextGroup+7 ; radio input filter

LIGHT1S .equ NextGroup+8 ; light timer for 1second flash
DOG2 .equ NextGroup+9 ; second watchdog
FAULTFLAG .equ NextGroup+10 ; flag for fault blink, no rad. blink
MOTDEL .equ NextGroup+11 ; motor time delay
POINT_DEB .equ NextGroup+12 ; Pass Point debouncer
DELAYC .equ NextGroup+13 ; for the time delay for command
LFA_C .equ NextGroup+14 ; Limits are changing register
CMP .equ NextGroup+15 ; Counter compare result

BACKUP_GRP .equ 0B0H
PCounterA .equ BACKUP_GRP
PCounterB .equ BACKUP_GRP+1
PCounterC .equ BACKUP_GRP+2
PCounterD .equ BACKUP_GRP+3
HOUR_TIMER .equ BACKUP_GRP+4
HOUR_TIMER_HI .equ BACKUP_GRP+4
HOUR_TIMER_LO .equ BACKUP_GRP+5
PassCounter .equ BACKUP_GRP+6
STACKREASON .equ BACKUP_GRP+7
FirstRun .equ BACKUP_GRP+8 ; Flag for first operation after power-up
MinSpeed .equ BACKUP_GRP+9
BRPM_COUNT .equ BACKUP_GRP+10
BRPM_TIME_OUT .equ BACKUP_GRP+11
BFORCE_IGNORE .equ BACKUP_GRP+12
BAUTO_DELAY .equ BACKUP_GRP+13
BCMD_DEB .equ BACKUP_GRP+14
BSTATE .equ BACKUP_GRP+15

; Double-mapped registers for M6800 test
COUNT_HI .equ BRPM_COUNT
COUNT_LO .equ BRPM_TIME_OUT
COUNT .equ BFORCE_IGNORE
REGTEMP .equ BAUTO_DELAY
REGTEMP2 .equ BCMD_DEB

; Double-mapped registers for Siminor Code Reception
CodeT0 .equ COUNT1L ; Binary radio code received
CodeT1 .equ RadiolL
CodeT2 .equ MirrorC
CodeT3 .equ MirrorD
CodeT4 .equ COUNT3H
CodeT5 .equ COUNT3L

Ix .equ COUNT1H ; Index per Siminor's code

WlHigh .equ AddValueH ; Word 1 per Siminor's code
WlLow .equ AddValueL ; description
wlhigh .equ addvalueh
wllow .equ addvalueL

```

[illegible]

```

        FILL10
        FILL10
        FILL10
        FILL10
        FILL10
        FILL10
        .endm

FILL1000 .macro
        FILL100
        FILL100
        FILL100
        FILL100
        FILL100
        FILL100
        FILL100
        FILL100
        FILL100
        FILL100
        FILL100
        .endm

TRAP .macro
        jp      start
        jp      start
        jp      start
        jp      start
        jp      start
        .endm

TRAP10 .macro
        TRAP
        TRAP
        TRAP
        TRAP
        TRAP
        TRAP
        TRAP
        TRAP
        TRAP
        TRAP
        .endm

SetRpToRadio2Group .macro
        .byte 031H
        .byte 080H
        .endm

```

```

;*****
;*
;* Interrupt Vector Table
;*
;*****

```

```

.org 0000H

.if TwoThirtyThree

.word RADIO_INT ;IRQ0
.word 000CH ;IRQ1, P3.3
.word RPM ;IRQ2, P3.1
.word AUX_OBS ;IRQ3, P3.0
.word TIMERUD ;IRQ4, T0
.word RS232 ;IRQ5, T1

.else

.word RADIO_INT ;IRQ0
.word RADIO_INT ;IRQ1, P3.3
.word RPM ;IRQ2, P3.1

```

```

.word AUX_OBS          ;IRQ3, P3.0
.word TIMERUD          ;IRQ4, T0
.word 000CH            ;IRQ5, T1

```

```

.ENDIF

```

```

.page
.org    000CH
jp      START          ;jumps to start at location 0101, 0202 etc

```

```

-----
; RS232 DATA ROUTINES
;

```

```

; RS_COUNTER REGISTER:

```

```

; 0000XXXX - 0011XXXX Input byte counter (inputting bytes 1-4)
; 00XX0000      Waiting for a start bit
; 00XX0001 - XXXX1001 Input bit counter (Bits 1-9, including stop)
; 00XX1111      Idle -- whole byte received
;
; 1000XXXX - 1111XXXX Output byte counter (outputting bytes 1-8)
; 1XXX0000      Tell the routine to output a byte
; 1XXX0001 - 1XXX1001 Outputting a byte (Bits 1-9, including stop)
; 1XXX1111      Idle -- whole byte output
;
-----

```

```

OutputMode:

```

```

    tm    RS_COUNTER, #00001111B      ; Check for outputting start bit
    jr    z, OutputStart              ;
    tcm    RS_COUNTER, #00001001B      ; Check for outputting stop bit
    jr    z, OutputStop                ; (bit 9), if so, don't increment

```

```

OutputData:

```

```

    scf                                ; Set carry to ensure high stop bit
    rrc    RS232DAT                    ; Test the bit for output
    jr    c, OutputHigh                ;

```

```

OutputLow:

```

```

    and    p3, #~CHARGE_SW             ; Turn off the pull-up
    or     p3, #DIS_SW                 ; Turn on the pull-down
    jr     DataBitDone                 ;

```

```

OutputStart:

```

```

    ld     T1, #RsPerFull               ; Set the timer to a full bit period
    ld     TMR, #00001110B              ; Load the full time period
    and    p3, #~CHARGE_SW              ; Send a start bit
    or     p3, #DIS_SW                  ;
    inc    RS_COUNTER                   ; Set the counter to first bit
    iret                                ;

```

```

OutputHigh:

```

```

    and    p3, #~DIS_SW                 ; Turn off the pull-down
    or     p3, #CHARGE_SW               ; Turn on the pull-up

```

```

DataBitDone:

```

```

    inc    RS_COUNTER                   ; Advance to the next data bit
    iret                                ;

```

```

OutputStop:

```

```

    and    p3, #~DIS_SW                 ; Output a stop (high) bit
    or     p3, #CHARGE_SW               ;

```



```

    or    RS_COUNTER, #00001111B    ; Set the flag for word being done
    cp    RS_COUNTER, #11111111B    ; Test for last output byte
    jr    nz, MoreOutput             ; If not, wait for more output
    clr    RS_COUNTER                ; Start waiting for input bytes
MoreOutput:
RSExit:
    ired

RS232:

    cp    RsMode, #00                ; Check for in RS232 mode,
    jr    nz, InRsMode               ; If so, keep receiving data
    cp    STATUS, #CHARGE            ; Else, only receive data when
    jr    nz, WallModeBad            ; charging the wall control

InRsMode:

    tcm    RS_COUNTER, #00001111B    ; Test for idle state
    jr    z, RSExit                 ; If so, don't do anything

    tm    RS_COUNTER, #11000000B     ; test for input or output mode
    jr    nz, OutputMode

RSInput:

    tm    RS_COUNTER, #00001111B     ; Check for waiting for start
    jr    z, WaitForStart           ; If so, test for start bit

    tcm    RS_COUNTER, #00001001B    ; Test for receiving the stop bit
    jr    z, StopBit                ; If so, end the word

    scf                                ; Initially set the data in bit
    tm    RS232IP, #RS232IM          ; Check for high or low bit at input
    jr    nz, GotRsBit              ; If high, leave carry high

    rcf                                ; Input bit was low

GotRsBit:

    rrc    RS232DAT                  ; Shift the bit into the byte
    inc    RS_COUNTER                ; Advance to the next bit
    ired

StopBit:

    tm    RS232IP, #RS232IM          ; Test for a valid stop bit
    jr    z, DataBad                ; If invalid, throw out the word

DataGood:

    tm    RS_COUNTER, #11110000B     ; If we're not reading the first word,
    jr    nz, IsData                ; then this is not a command
    ld     RSCOMMAND, RS232DAT        ; Load the new command word

IsData:

    or     RS_COUNTER, #00001111B    ; Indicate idle at end of word
    ired

WallModeBad:

    clr    RS_COUNTER                ; Reset the RS232 state

DataBad:

    and    RS_COUNTER, #00110000B    ; Clear the byte counter
    ired

WaitForStart:

    tm    RS232IP, #RS232IM          ; Check for a start bit

```

```

        jr      nz, NoStartBit                ; If high, keep waiting

        inc     RS_COUNTER                    ; Set to receive bit 1
        ld      T1, #RsPer1P22               ; Long time until next sample
        ld      TMR, #00001110B              ; Load the timer
        ld      T1, #RsPerFull                ; Sample at 1X afterwards
        iredt                                  ;

NoStartBit:

        ld      T1, #RsPerHalf                ; Sample at 2X for start bit
        iredt

;-----
;   Set the worklight timer to 4.5 minutes for 60Hz line
;   and 2.5 minutes for 50 Hz line
;-----
SetVarLight:
        cp      LinePer, #36                  ; Test for 50Hz or 60Hz
        jr      uge, EuroLight                ; Load the proper table
USALight:
        ld      LIGHT_TIMER_HI, #USA_LIGHT_HI ; set the light period
        ld      LIGHT_TIMER_LO, #USA_LIGHT_LO ;
        ret                                         ; Return
EuroLight:
        ld      LIGHT_TIMER_HI, #EURO_LIGHT_HI ; set the light period
        ld      LIGHT_TIMER_LO, #EURO_LIGHT_LO ;
        ret                                         ; Return

;-----
;   THIS THE AUXILARY OBSTRUCTION INTERRUPT ROUTINE
;-----
AUX_OBS:
        ld      OBS_COUNT, #11                ; reset pulse counter (no obstruction)
        and     imr, #11110111b              ; turn off the interrupt for up to 500uS
        ld      AOBSTEST, #11                 ; reset the test timer
        or      AOBSF, #000000010B           ; set the flag for got a aobs
        and     AOBSF, #11011111B            ; Clear the bad aobs flag
        iredt                                  ; return from int

;-----
;   Test for the presence of a blinker module
;-----
LookForFlasher:
        and     P2M_SHADOW, #~BLINK_PIN       ; Set high for autolatch test
        ld      P2M, P2M_SHADOW               ;
        or      P2, #BLINK_PIN                ;
        or      P2M_SHADOW, #BLINK_PIN        ; Look for Flasher module
        ld      P2M, P2M_SHADOW               ;
        ret

; Fill 41 bytes of unused memory

FILL10
FILL10
FILL10
FILL10
FILL

;*****
; REGISTER INITIALIZATION
;*****

.org     0101H                                ; address has both bytes the same
start:
START: di                                     ; turn off the interrupt for init

.IF     TwoThirtyThree

```

```

ld    RP,#WATCHDOG_GROUP
ld    wdtmr,#00001111B          ; rc dog 100ms

.ELSE

clr    P1

.ENDIF

WDT                                ; kick the dog
clr    RP                        ; clear the register pointer

;*****
; PORT INITIALIZATION
;*****

ld    P0,#P01S_INIT              ; RESET all ports
ld    P2,#P2S_POR                ; Output the chip ID code
ld    P3,#P3S_INIT              ;
ld    P01M,#P01M_INIT            ; set mode p00-p03 out p04-p07in
ld    P3M,#P3M_INIT             ; set port3 p30-p33 input analog mode
                                   ; p34-p37 outputs
ld    P2M,#P2M_POR              ; set port 2 mode for chip ID out

;*****
; Internal RAM Test and Reset All RAM = mS *
;*****
    srp    #0F0h                 ; point to control group use stack
    ld     r15,#4                ; r15= pointer (minimum of RAM)
write_again:
    WDT                                ; KICK THE DOG
    ld     r14,#1
write_again1:
    ld     @r15,r14              ;write 1,2,4,8,10,20,40,80
    cp     r14,@r15              ;then compare
    jr     ne,system_error
    rl     r14
    jr     nc,write_again1
    clr    @r15                  ;write RAM(r5)=0 to memory
    inc    r15
    cp     r15,#240
    jr     ult,write_again

;*****
; *      Checksum Test      *
;*****
CHECKSUMTEST:
    srp    #CHECK_GRP
    ld     test_adr_hi,#01FH
    ld     test_adr_lo,#0FFH      ;maximum address=ffff
add_sum:
    WDT                                ; KICK THE DOG
    ldc    rom_data,@test_adr     ;read ROM code one by one
    add    check_sum,rom_data     ;add it to checksum register
    decw   test_adr               ;increment ROM address
    jr     nz,add_sum             ;address=0 ?
    cp     check_sum,#check_sum_value
    jr     z,system_ok            ;check final checksum = 00 ?
system_error:
    and    ledport,#led1          ; turn on the LED to indicate fault
    jr     system_error

    .byte 256-check_sum_value
system_ok:

```

```

WDT                                ; kick th dog

ld    STACKEND,#STACKTOP          ; start at the top of the stack
SETSTACKLOOP:
ld    @STACKEND,#01H              ; set the value for the stack vector
dec    STACKEND                  ; next address
cp    STACKEND,#STACKEND         ; test for the last address
jr    nz,SETSTACKLOOP           ; loop till done

CLEARDONE:

; ld    STATE,#06                ; set the state to stop
; ld    BSTATE,#06
; ld    OnePass,STATE            ; Set the one-shot
ld    STATUS,#CHARGE             ; set start to charge
ld    SWITCH_DELAY,#CMD_DEL_EX   ; set the delay time to cmd
ld    LIGHT_TIMER_HI,#USA_LIGHT_HI ; set the light period
ld    LIGHT_TIMER_LO,#USA_LIGHT_LO ; for the 4.5 min timer
ld    RPMONES,#244              ; set the hold off
srp    #LEARNEE_GRP
ld    learndb,#OFFH             ; set the learn debouncer
ld    zzwin,learndb             ; turn off the learning
ld    CMD_DEB,learndb           ; in case of shorted switches
ld    BCMD_DEB,learndb          ; in case of shorted switches
ld    VAC_DEB,learndb
ld    LIGHT_DEB,learndb
ld    ERASET,learndb            ; set the erase timer
ld    learnt,learndb            ; set the learn timer
ld    RTO,learndb               ; set the radio time out
ld    AUXLEARNSW,learndb        ; turn off the aux learn switch
ld    RRTO,learndb              ; set the radio timer

; *****
; STACK INITIALIZATION
; *****
clr    254
ld    255,#236                  ; set the start of the stack
.if    TwoThirtyThree
.ELSE
clr    P1
.ENDIF

; *****
; TIMER INITIALIZATION
; *****

ld    PRE0,#00000101B           ; set the prescaler to /1 for 4MHz
ld    PRE1,#00010011B           ; set the prescaler to /4 for 4MHz
clr    T0                       ; set the counter to count FF through 0
ld    T1,#RsPerHalf             ; set the period to rs232 period for start bit sample
ld    TMR,#00001111B           ; turn on the timers

; *****
; PORT INITIALIZATION
; *****

ld    P0,#P01S_INIT             ; RESET all ports
ld    P2,#P2S_INIT
ld    P3,#P3S_INIT
ld    P01M,#P01M_INIT           ; s t mode p00-p03 out p04-p07in
ld    P3M,#P3M_INIT             ; set port3 p30-p33 input analog mode
                                   ; p34-p37 outputs
ld    P2M_SHADOW,#P2M_INIT      ; Shadow P2M for read ability
ld    P2M,#P2M_INIT            ; set port 2 mode

.if    TwoThirtyThree
.ELSE

```

```

clr    P1
.ENDIF

;*****
; READ THE MEMORY 2X AND GET THE VACFLAG
;*****

ld      SKIPRADIO, #NOEECOMM      ;
ld      ADDRESS, #VACATIONADDR    ; set non vol address to the VAC flag
call    READMEMORY                ; read the value 2X 1X INIT 2ND read
call    READMEMORY                ; read the value
ld      VACFLAG, MTEMPH           ; save into volital

WakeUpLimits:
ld      ADDRESS, #UPLIMADDR        ; Read the up and down limits into memory
call    READMEMORY                ;
ld      UP_LIMIT_HI, MTEMPH        ;
ld      UP_LIMIT_LO, MTEMPH        ;
ld      ADDRESS, #DNLMADDR        ;
call    READMEMORY                ;
ld      DN_LIMIT_HI, MTEMPH        ;
ld      DN_LIMIT_LO, MTEMPH        ;
WDT                                ; Kick the dog

WakeUpState:
ld      ADDRESS, #LASTSTATEADDR    ; Read the previous operating state into memory
call    READMEMORY                ;
ld      STATE, MTEMPH              ; Load the state
ld      PassCounter, MTEMPH        ; Load the pass point counter
cp      STATE, #UP_POSITION        ; If at up limit, set position
jr      z, WakeUpLimit            ;
cp      STATE, #DN_POSITION        ; If at down limit, set position
jr      z, WakeDnLimit            ;

WakeUpLost:
ld      STATE, #STOP               ; Set state as stopped in mid travel
ld      POSITION_HI, #07FH          ; Set position as lost
ld      POSITION_LO, #080H          ;
jr      GotWakeUp                 ;

WakeUpLimit:
ld      POSITION_HI, UP_LIMIT_HI    ; Set position as at the up limit
ld      POSITION_LO, UP_LIMIT_LO    ;
jr      GotWakeUp                 ;

WakeDnLimit:
ld      POSITION_HI, DN_LIMIT_HI    ; Set position as at the down limit
ld      POSITION_LO, DN_LIMIT_LO    ;

GotWakeUp:
ld      BSTATE, STATE              ; Back up the state and
ld      OnePass, STATE             ; clear the one-shot

;*****
; SET ROLLING/FIXED MODE FROM NON-VOLATILE MEMORY
;*****

call    SetRadioMode              ; Set the radio mode
jr      SETINTERRUPTS            ; Continue on

SetRadioMode:
ld      SKIPRADIO, #NOEECOMM        ; Set skip radio flag
ld      ADDRESS, #MODEADDR          ; Point to the radio mode flag
call    READMEMORY                ; Read the radio mode
ld      RadioMode, MTEMPH          ; Set the proper radio mode

```

```

clr    SKIPRADIO                      ; Re-enable the radio
tm     RadioMode, #ROLL_MASK          ; Do we want rolling numbers
jr     nz, StartRoll

call   FixedNums
ret

```

StartRoll:

```

call   RollNums
ret

```

; *****
; INITERRUPT INITIALIZATION
; *****

SETINTERRUPTS:

```

ld     IPR,#00011010B                ; set the priority to timer
ld     IMR,#ALL_ON_IMR                ; turn on the interrupt

.IF    TwoThirtyThree
ld     IRQ,#01000000B                ; set the edge clear int
.ELSE
ld     IRQ,#00000000b                ; Set the edge, clear ints
.ENDIF

ei                                         ; enable interrupt

```

; *****
RESET SYSTEM REG
; *****

```

.IF    TwoThirtyThree

ld     RP,#WATCHDOG_GROUP
ld     smr,#00100010B                ; reset the xtal / number
ld     pcon,#01111110B                ; reset the pcon no comparator output
                                           ; no low emi mode
clr     RP                            ; Reset the RP

.ENDIF

ld     PRE0,#00000101B                ; set the prescaler to / 1 for 4Mhz
WDT                                           ; Kick the dog

```

; *****
; MAIN LOOP
; *****

MAINLOOP:

```

cp     PrevPass, PassCounter          ;Compare pass point counter to backup
jr     z, PassPointCurrent            ;If equal, EEPROM is up to date

```

PassPointChanged:

```

ld     SKIPRADIO, #NOEECOMM           ; Disable radio EEPROM communications
ld     ADDRESS, #LASTSTATEADDR        ; Point to the pass point storage
call   READMEMORY                     ; Get the current GDO state
di                                           ; Lock in the pass point state
ld     MTEMPH, PassCounter            ; Store the current pass point state
ld     PrevPass, PassCounter          ; Clear the one-shot
ei
call   WRITEMEMORY                    ; Write it back to the EEPROM
clr     SKIPRADIO

```

PassPointCurrent:

; 4-22-97

```

CP      EnableWorkLight,#10000000B ;is the debouncer set? if so write and
                                           ;give feedback

JR      NE,LightOpen
TM      p0,#LIGHT_ON
JR      NZ,GetRidOfIt
LD      MTEMPL,#0FFH                ;turn on the IR beam work light function
LD      MTEMPH,#0FFH
JR      CommitToMem

GetRidOfIt:
LD      MTEMPL,#00H                ;turn off the IR beam work light function
LD      MTEMPH,#00H

CommitToMem:
LD      SKIPRADIO,#NOEECOMM        ;write to memory to store if enabled or not
LD      ADDRESS,#IRLIGHTADDR       ;set address for write
CALL    WRITEMEMORY
CLR     SKIPRADIO
XOR     p0,#WORKLIGHT              ;toggle current state of work light for feedback
LD      EnableWorkLight,#01100000B
;

LightOpen:
cp      LIGHT_TIMER_HI,#0FFH        ; if light timer not done test beam break
jr      nz,TestBeamBreak
tm      p0,#LIGHT_ON                ; if the light is off test beam break
jr      nz,LightSkip

TestBeamBreak:
tm      AOBSF,#10000000b            ; Test for broken beam
jr      z,LightSkip                 ; if no pulses Staying blocked
                                           ; else we are intermittent

4-22-97
LD      SKIPRADIO,#NOEECOMM        ;Trun off radio interrupt to read from e2
LD      ADDRESS,#IRLIGHTADDR
CALL    READMEMORY
CLR     SKIPRADIO                    ; don't forget to zero the one shot
CP      MTEMPL,#DISABLED            ; Does e2 report that IR work light function
JR      EQ,LightSkip                ; is disabled? IF so jump over light on and

cp      STATE,#2                    ; test for the up limit
jr      nz,LightSkip                ; if not goto output the code
call    SetVarLight                 ; Set worklight to proper time
or      p0,#LIGHT_ON                ; turn on the light

LightSkip:
4-22-97
AND     AOBSF,#01111111B            ;Clear the one shot,for IR beam
                                           ;break detect.

;

cp      HOUR_TIMER_HI, #01CH        ; If an hour has passed,
jr      ult, NoDecrement             ; then decrement the
cp      HOUR_TIMER_LO, #020H        ; temporary password timer
jr      ult, NoDecrement             ;

clr     HOUR_TIMER_HI                ; Reset hour timer
clr     HOUR_TIMER_LO
ld      SKIPRADIO,#NOEECOMM        ; Disable radio EE read
ld      ADDRESS,#DURAT              ; Load the temporary password
call    READMEMORY                  ; duration from non-volatile
cp      MTEMPH,#HOURS                ; If not in timer mode,
jr      nz, NoDecrement2             ; then don't update
cp      MTEMPL,#00                   ; If timer is not done,
jr      z, NoDecrement2              ; decrement it

dec     MTEMPL                       ; Update the number of hours
call    WRITEMEMORY

NoDecrement:

tm      AOBSF, #01000000b            ; If the poll radio mode flag is
jr      z, NoDecrement2              ; set, poll the radio mode

```

```

call SetRadioMode          ; Set the radio mode
and AOBSF, #10111111b     ; Clear the flag

NoDecrement2:

clr SKIPRADIO              ; Re-enable radio reads
and AOBSF, #00100011b     ; Clear the single break flag
clr DOG2                   ; clear the second watchdog
ld P01M, #P01M_INIT       ; set mode p00-p03 out p04-p07in
ld P3M, #P3M_INIT         ; set port3 p30-p33 input analog mode
                           ; p34-p37 outputs
or P2M_SHADOW, #P2M_ALLINS ; Refresh all the P2M pins which have are
and P2M_SHADOW, #P2M_ALLOUTS ; always the same when we get here
ld P2M, P2M_SHADOW        ; set port 2 mode
cp VACCHANGE, #0AAH       ; test for the vacation change flag
jr nz, NOVACCHG           ; if no change the skip
cp VACFLAG, #0FFH         ; test for in vacation
jr z, MCLEARVAC          ; if in vac clear
ld VACFLAG, #0FFH        ; set vacation
jr SETVACCHANGE          ; set the change

MCLEARVAC:
clr VACFLAG               ; clear vacation mode

SETVACCHANGE:
clr VACCHANGE             ; one shot
ld SKIPRADIO, #NOEECOMM   ; set skip flag
ld ADDRESS, #VACATIONADDR ; set the non vol address to the VAC flag
ld MTEMPH, VACFLAG        ; store the vacation flag
ld MTEMPL, VACFLAG        ;
call WRITEMEMORY          ; write the value
clr SKIPRADIO             ; clear skip flag

NOVACCHG:
cp STACKFLAG, #0FFH      ; test for the change flag
jr nz, NOCHANGEST        ; if no change skip updating

cp L_A_C, #070H          ; If we're in learn mode
jr uge, SkipReadLimits   ; then don't refresh the limits!

cp STATE, #UP_DIRECTION  ; If we are going to travel up
jr z, ReadUpLimit        ; then read the up limit

cp STATE, #DN_DIRECTION  ; If we are going to travel down
jr z, ReadDnLimit        ; then read the down limit

jr SkipReadLimits        ; No limit on this travel...

ReadUpLimit:

ld SKIPRADIO, #NOEECOMM   ; Skip radio EEPROM reads
ld ADDRESS, #UPLIMADDR    ; Read the up limit
call READMEMORY           ;
di                         ;
ld UP_LIMIT_HI, MTEMPH    ;
ld UP_LIMIT_LO, MTEMPL    ;
clr FirstRun              ; Calculate the highest possible value for pass count
add MTEMPL, #10           ; Bias back by 1" to provide margin of error
adc MTEMPH, #00           ;

CalcMaxLoop:
inc FirstRun              ;
add MTEMPL, #LOW(PPOINTPULSES) ;
adc MTEMPH, #HIGH(PPOINTPULSES) ;
jr nc, CalcMaxLoop        ; Count pass points until value goes positive

GotMaxPPoint:
ei                         ;
clr SKIPRADIO             ;
tm PassCounter, #01000000b ; Test for a negative pass point counter
jr z, CounterGood1        ; If not, no lower bounds check needed
cp DN_LIMIT_HI, #HIGH(PPOINTPULSES - 35) ; If the down limit is low enough,
jr ugt, CounterIsNeg1     ; then the counter can be negative

```



```

        jr      ult, ClearCount          ; Else, it should be zero
        cp      DN_LIMIT_LO, #LOW(PPOINTPULSES - 35)
        jr      uge, CounterIsNegl      ;
ClearCount:
        and     PassCounter, #10000000b      ; Reset the pass point counter to zero
        jr      CounterGood1
CounterIsNegl:
        or      PassCounter, #01111111b      ; Set the pass point counter to -1
CounterGood1:
        cp      UP_LIMIT_HI, #0FFH          ; Test to make sure up limit is at a
        jr      nz, TestUpLimit2            ; a learned and legal value
        cp      UP_LIMIT_LO, #0FFH          ;
        jr      z, LimitIsBad               ;
        jr      LimitsAreDone               ;
TestUpLimit2:
        cp      UP_LIMIT_HI, #0D0H          ; Look for up limit set to illegal value
        jr      ule, LimitIsBad             ; If so, set the limit fault
        jr      LimitsAreDone               ;

ReadDnLimit:
        ld      SKIPRADIO, #NOEECOMM        ; Skip radio EEPROM reads
        ld      ADDRESS, #DNLIMITADDR       ; Read the down limit
        call    READMEMORY
        di
        ld      DN_LIMIT_HI, MTEMPH         ;
        ld      DN_LIMIT_LO, MTEMPL         ;
        ei
        clr     SKIPRADIO
        cp      DN_LIMIT_HI, #00H           ;
        jr      nz, TestDownLimit2          ; Test to make sure down limit is at a
        cp      DN_LIMIT_LO, #00H           ; a learned and legal value
        jr      z, LimitIsBad               ;
        jr      LimitsAreDone               ;
TestDownLimit2:
        cp      DN_LIMIT_HI, #020H          ; Look for down limit set to illegal value
        jr      ult, LimitsAreDone          ; If not, proceed as normal
LimitIsBad:
        ld      FAULTCODE, #7               ; Set the "no limits" fault
        call    SET_STOP_STATE              ; Stop the GDO
        jr      LimitsAreDone               ;

SkipReadLimits:
LimitsAreDone:
        ld      SKIPRADIO, #NOEECOMM        ; Turn off the radio read
        ld      ADDRESS, #LASTSTATEADDR     ; Write the current state and pass count
        call    READMEMORY
        ld      MTEMPH, PassCounter         ; DON'T update the pass point here!
        ld      MTEMPL, STATE
        call    WRITEMEMORY
        clr     SKIPRADIO
        ld      OnePass, STATE              ; Clear the one-shot

        cp      L_A_C, #077H                ; Test for successful learn cycle
        jr      nz, DontWriteLimits         ; If not, skip writing limits
WriteNewLimits:
        cp      STATE, #STOP
        jr      nz, WriteUpLimit
        cp      LIM_TEST_HI, #00            ; Test for (force) stop within 0.5" of
        jr      nz, WriteUpLimit            ; the original up limit position
        cp      LIM_TEST_LO, #06
        jr      ugt, WriteUpLimit
BackOffUpLimit:
        add     UP_LIMIT_LO, #06            ; Back off the up limit by 0.5"
        adc     UP_LIMIT_HI, #00
WriteUpLimit:
        ld      SKIPRADIO, #NOEECOMM        ; Skip radio EEPROM reads

```

```

ld    ADDRESS, #UPLIMADDR    ; Read the up limit
di
ld    MTEMPH, UP_LIMIT_HI    ;
ld    MTEMPL, UP_LIMIT_LO    ;
ei
call  WRITEMEMORY            ;
WriteDnLimit:
ld    ADDRESS, #DNLIMADDR    ; Read the up limit
di
ld    MTEMPH, DN_LIMIT_HI    ;
ld    MTEMPL, DN_LIMIT_LO    ;
ei
call  WRITEMEMORY            ;
WritePassCount:
ld    ADDRESS, #LASTSTATEADDR    ; Write the current state and pass count
ld    MTEMPH, PassCounter    ; Update the pass point
ld    MTEMPL, STATE          ;
call  WRITEMEMORY            ;
clr   SKIPRADIO              ;
clr   L_A_C                  ; Leave the learn mode
or    ledport, #ledh          ; turn off the LED for program mode

DontWriteLimits:
srp   #LEARNER_GRP            ; set the register pointer
clr   STACKFLAG               ; clear the flag
ld    SKIPRADIO, #NOEECOMM     ; set skip flag
ld    address, #CYCCOUNT       ; set the non vol address to the cycle c
call  READMEMORY              ; read the value
inc   mtempl                  ; increase the counter lower byte
jr    nz, COUNTER1DONE         ;
inc   mtempH                  ; increase the counter high byte
jr    nz, COUNTER2DONE         ;
call  WRITEMEMORY              ; store the value
inc   address                 ; get the next bytes
call  READMEMORY              ; read the data
inc   mtempl                  ; increase the counter low byte
jr    nz, COUNTER2DONE         ;
inc   mtempH                  ; increase the vounter high byte
COUNTER2DONE:
call  WRITEMEMORY              ; save the value
ld    address, #CYCCOUNT       ;
call  READMEMORY              ; read the data

and   mtempH, #00001111B       ; find the force address
or    mtempH, #30H             ;
ld    ADDRESS, MTEMPH          ; set the address
ld    mtempl, DNFORCE          ; read the forces
ld    mtempH, UPFORCE          ;
call  WRITEMEMORY              ; write the value
jr    CDONE                    ; done set the back trace
COUNTER1DONE:
call  WRITEMEMORY              ; got the new address
CDONE:
clr   SKIPRADIO               ; clear skip flag

NOCHANGEST:
call  LEARN                    ; do the learn switch
di
cp    BRPM_COUNT, RPM_COUNT
jr    z, TESTRPM

RESET:
jp    START

TESTRPM:
cp    BRPM_TIME_OUT, RPM_TIME_OUT
jr    nz, RESET
cp    BFORCE_IGNORE, FORCE_IGNORE
jr    nz, RESET
ei

```

```

di
cp    BAUTO_DELAY,AUTO_DELAY
jr    nz,RESET
cp    BCMD_DEB,CMD_DEB
jr    nz,RESET
cp    BSTATE,STATE
jr    nz,RESET
ei

TESTRS232:
SRP    #TIMER_GROUP
tcm    RS_COUNTER, #00001111B
jp     nz, SKIPRS232                ; If we are at the end of a word,
                                    ; then handle the RS232 word

cp     rscommand,#'V'                ;
jp     ugt,ClearRS232                ;
cp     rscommand,#'0'                ; test for in range
jp     ult,ClearRS232                ; if out of range skip
cp     rscommand,#'<'                ; If we are reading
jr     nz,NotRs3C                    ; go straight there
call   GotRs3C                       ;
jp     SKIPRS232                     ;

NotRs3C:
cp     rscommand,#'>'                ; If we are writing EEPROM
jr     nz,NotRs3E                    ; go straight there
call   GotRs3E                       ;
jp     SKIPRS232                     ;

NotRs3E:
ld     rs_temp_hi,#HIGH (RS232JumpTable-(3*'0'))    ; address pointer to table
ld     rs_temp_lo,#LOW (RS232JumpTable-(3*'0'))      ; Offset for ASCII adjust

add     rs_temp_lo,rscommand            ; look up the jump 3x
adc     rs_temp_hi,#00                  ;
add     rs_temp_lo,rscommand            ; look up the jump 3x
adc     rs_temp_hi,#00                  ;
add     rs_temp_lo,rscommand            ; look up the jump 3x
adc     rs_temp_hi,#00                  ;
call    @rs_temp                        ; call this address
jp      SKIPRS232                      ; done

RS232JumpTable:
jp      GotRs30
jp      GotRs31
jp      GotRs32
jp      GotRs33
jp      GotRs34
jp      GotRs35
jp      GotRs36
jp      GotRs37
jp      GotRs38
jp      GotRs39
jp      GotRs3A
jp      GotRs3B
jp      GotRs3C
jp      GotRs3D
jp      GotRs3E
jp      GotRs3F
jp      GotRs40
jp      GotRs41
jp      GotRs42
jp      GotRs43
jp      GotRs44
jp      GotRs45
jp      GotRs46
jp      GotRs47
jp      GotRs48
jp      GotRs49
jp      GotRs4A
jp      GotRs4B
jp      GotRs4C

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jp    GotRs4D
jp    GotRs4E
jp    GotRs4F
jp    GotRs50
jp    GotRs51
jp    GotRs52
jp    GotRs53
jp    GotRs54
jp    GotRs55
jp    GotRs56

```

ClearRS232:

```

and    RS_COUNTER, #11110000b           ; Clear the RS232 state

```

SKIPRS232:

UpdateForceAndSpeed:

```

; Update the UP force from the look-up table

```

```

srp    #FORCE_GROUP                     ; Point to the proper registers
ld     force_add_hi, #HIGH(force_table) ; Fetch the proper unscaled
ld     force_add_lo, #LOW(force_table)  ; value from the ROM table
di
add     force_add_lo, upforce            ; Offset to point to the
adc     force_add_hi, #00                ; proper place in the table
add     force_add_lo, upforce            ; x2
adc     force_add_hi, #00                ;
add     force_add_lo, upforce            ; x3 (three bytes wide)
adc     force_add_hi, #00                ;
ei
;

ldc     force_temp_of, @force_add        ; Fetch the ROM bytes
incw    force_add                       ;
ldc     force_temp_hi, @force_add        ;
incw    force_add                       ;
ldc     force_temp_lo, @force_add        ;

ld     Divisor, PowerLevel              ; Divide by our current force level
call    ScaleTheSpeed                   ; Scale to get our proper force number

di
ld     UP_FORCE_HI, force_temp_hi        ;
ld     UP_FORCE_LO, force_temp_lo        ;
ei
;

```

```

; Update the DOWN force from the look-up table

```

```

ld     force_add_hi, #HIGH(force_table) ; Fetch the proper unscaled
ld     force_add_lo, #LOW(force_table)  ; value from the ROM table
di
add     force_add_lo, dnforce            ; Offset to point to the
adc     force_add_hi, #00                ; proper place in the table
add     force_add_lo, dnforce            ; x2
adc     force_add_hi, #00                ;
add     force_add_lo, dnforce            ; x3 (three bytes wide)
adc     force_add_hi, #00                ;
ei
;

ldc     force_temp_of, @force_add        ; Fetch the ROM bytes
incw    force_add                       ;
ldc     force_temp_hi, @force_add        ;
incw    force_add                       ;
ldc     force_temp_lo, @force_add        ;

ld     Divisor, PowerLevel              ; Divide by our current force level
call    ScaleTheSpeed                   ; Scale to get our proper force number

```

```

di                                ; Update the force registers
ld  DN_FORCE_HI, force_temp_hi  ;
ld  DN_FORCE_LO, force_temp_lo  ;
ei                                ;

; Scale the minimum speed based on force setting
cp  STATE, #DN_DIRECTION        ; If we're traveling down,
jr  z, SetDownMinSpeed          ; then use the down force pot for min. speed

SetUpMinSpeed:
di                                ; Disable interrupts during update
ld  MinSpeed, UPFORCE           ; Scale up force pot
jr  MinSpeedMath                ;

SetDownMinSpeed:
di                                ;
ld  MinSpeed, DNFORCE           ; Scale down force pot

MinSpeedMath:
sub  MinSpeed, #24              ; pot level - 24
jr  nc, UpStep2                 ; truncate off the negative number
clr  MinSpeed                   ;

UpStep2:
rcf                                ; Divide by four
rrc  MinSpeed                   ;
rcf                                ;
rrc  MinSpeed                   ;
add  MinSpeed, #4               ; Add four to find the minimum speed
cp  MinSpeed, #12               ; Perform bounds check on minimum speed,
jr  ule, MinSpeedOkay          ; Truncate if necessary
ld  MinSpeed, #12               ;

MinSpeedOkay:
ei                                ; Re-enable interrupts

; Make sure the worklight is at the proper time on power-up

cp  LinePer, #36                ; Test for a 50 Hz system
jr  ult, TestRadioDeadTime      ; if not, we don't have a problem
cp  LIGHT_TIMER_HI, #OFFH        ; If the light timer is running
jr  z, TestRadioDeadTime        ; and it is greater than
cp  LIGHT_TIMER_HI, #EURO_LIGHT_HI ; the European time, fix it
jr  ule, TestRadioDeadTime      ;
call SetVarLight                ;

TestRadioDeadTime:
cp  R_DEAD_TIME, #25            ; test for too long dead
jp  nz, MAINLOOP                ; if not loop
clr  RadioC                     ; clear the radio counter
clr  RFlag                      ; clear the radio flag
jp  MAINLOOP                    ; loop forever

;-----
; Speed scaling (i.e. Division) routine
;-----

ScaleTheSpeed:

clr  TestReg
ld  loopreg, #24                ; Loop for all 24 bits

DivideLoop:
rcf                                ; Rotate the next bit into
rlc  force_temp_lo              ; the test field
rlc  force_temp_hi              ;
rlc  force_temp_of              ;
rlc  TestReg                    ;
cp  TestReg, Divisor            ; Test to see if we can subtract
jr  ult, BitIsDone              ; If we can't, we're all done
sub  TestReg, Divisor           ; Subtract the divisor
or  force_temp_lo, #00000001b   ; Set the LSB to mark the subtract

BitIsDone:
djnz loopreg, DivideLoop        ; Loop for all bits

```

```

DivideDone:
    ; Make sure the result is under our 500 ms limit
    cp    force_temp_of, #00                ; Overflow byte must be zero
    jr    nz, ScaleDown                    ;
    cp    force_temp_hi, #0F4H              ;
    jr    ugt, ScaleDown                    ;
    jr    ult, DivideIsGood                 ; If we're less, then we're okay
    cp    force_temp_lo, #024H              ; Test low byte
    jr    ugt, ScaleDown                    ; if low byte is okay,

DivideIsGood:
    ret                                     ; Number is good

ScaleDown:
    ld    force_temp_hi, #0F4H              ; Overflow is never used anyway
    ld    force_temp_lo, #024H              ;
    ret

;*****
; RS232 SUBROUTINES
;*****

; "0"
; Set Command Switch
GotRs30:
    ld    LAST_CMD, #0AAH                  ; set the last command as rs wall cmd
    call  CmdSet                           ; set the command switch
    jp    NoPos

; "1"
; Clear Command Switch
GotRs31:
    call  CmdRel                           ; release the command switch
    jp    NoPos

; "2"
; Set Worklight Switch
GotRs32:
    call  LightSet                         ; set the light switch
    jp    NoPos

; "3"
; Clear Worklight Switch
GotRs33:
    clr   LIGHT_DEB                       ; Release the light switch
    jp    NoPos

; "4"
; Set Vacation Switch
GotRs34:
    call  VacSet                           ; Set the vacation switch
    jp    NoPos

; "5"
; Clear Vacation Switch
GotRs35:
    clr   VAC_DEB                         ; release the vacation switch
    jp    NoPos

; "6"
; Set smart switch
GotRs36:
    call  SmartSet
    jp    NoPos

; "7"
; Clear Smart switch set
GotRs37:

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```

        call    SmartRelease
        jp      NoPos

; "8"
; Return Present state and reason for that state
GotRs38:
        ld      RS232DAT, STATE
        or      RS232DAT, STACKREASON
        jp      LastPos

; "9"
; Return Force Adder and Fault
GotRs39:
        ld      RS232DAT, FAULTCODE          ; insert the fault code
        jp      LastPos

; ":"
; Status Bits
GotRs3A:
        clr     RS232DAT                    ; Reset data
        tm      P2, #01000000b              ; Check the strap
        jr      z, LookForBlink             ; If none, next check
        or      RS232DAT, #00000001b        ; Set flag for strap high

LookForBlink:
        call    LookForFlasher
        tm      P2, #BLINK_PIN              ; If flasher is present,
        jr      nz, ReadLight               ; then indicate it
        or      RS232DAT, #00000010b

ReadLight:
        tm      P0, #00000010b              ; read the light
        jr      z, C3ADone
        or      RS232DAT, #00000100b

C3ADone:
        cp      CodeFlag, #REGLEARN         ; Test for being in a learn mode
        jr      ult, LookForPass            ; If so, set the bit
        or      RS232DAT, #00010000b

LookForPass:
        tm      PassCounter, #01111111b     ; Check for above pass point
        jr      z, LookForProt              ; If so, set the bit
        tcm     PassCounter, #01111111b
        jr      z, LookForProt
        or      RS232DAT, #00100000b

LookForProt:
        tm      AOBSF, #10000000b           ; Check for protector break/block
        jr      nz, LookForVac              ; If blocked, don't set the flag
        or      RS232DAT, #01000000b        ; Set flag for protector signal good

LookForVac:
        cp      VACFLAG, #00B               ; test for the vacation mode
        jp      nz, LastPos
        or      RS232DAT, #00001000b
        jp      LastPos

; ";"
; Return L_A_C
GotRs3B:
        ld      RS232DAT, L_A_C             ; read the L_A_C
        jp      LastPos

```

```

; "<"
; Read a word of data from an EEPROM address input by the user
GotRs3C:
    cp    RS_COUNTER, #010H          ; If we have only received the
    jr    ult, FirstByte             ; first word, wait for more
    cp    RS_COUNTER, #080H          ; If we are outputting,
    jr    ugt, OutputSecond           ; output the second byte

SecondByte:

    ld    SKIPRADIO, #0FFH           ; Read the memory at the specified
    ld    ADDRESS, RS232DAT           ; address
    call  READMEMORY                  ;
    ld    RS232DAT, MTEMPH            ; Store into temporary registers
    ld    RS_TEMP_LO, MTEMPH
    clr   SKIPRADIO
    jp    MidPos

OutputSecond:

    ld    RS232DAT, RS_TEMP_LO        ; Output the second byte of the read
    jp    LastPos

FirstByte:

    inc   RS_COUNTER                  ; Set to receive second word
    ret

; "="
Exit learn limits mode
GotRs3D:
    cp    L_A_C, #00                  ; If not in learn mode,
    jp    z, NoPos                    ; then don't touch the learn LED
    clr   L_A_C                       ; Reset the learn limits state machine
    or    ledport, #ledh              ; turn off the LED for program mode
    jp    NoPos

; ">"
Write a word of data to the address input by the user
GotRs3E:

    cp    RS_COUNTER, #01FH           ;
    jr    z, SecondByteW              ;
    cp    RS_COUNTER, #02FH           ;
    jr    z, ThirdByteW               ;
    cp    RS_COUNTER, #03FH           ;
    jr    z, FourthByteW              ;

FirstByteW:
DataDone:

    inc   RS_COUNTER                  ; Set to receive next byte
    ret

SecondByteW:

    ld    RS_TEMP_HI, RS232DAT        ; Store the address
    jr    DataDone

ThirdByteW:

    ld    RS_TEMP_LO, RS232DAT        ; Store the high byte
    jr    DataDone

FourthByteW:

    cp    RS_TEMP_HI, #03FH           ; Test for illegal address
    jr    ugt, FailedWrite            ; If so, don't write

```



```

ld    SKIPRADIO, #0FFH      ; Turn off radio reads
ld    ADDRESS, RS_TEMP_HI   ; Load the address
ld    MTEMPH, RS_TEMP_LO    ; and the data for the
ld    MTEMPL, RS232DAT       ; EEPROM write
call  WRITEMEMORY           ;
clr    SKIPRADIO            ; Re-enable radio reads
ld    RS232DAT, #00H        ; Flag write okay
jp     LastPos              ;

FailedWrite:

ld    RS232DAT, #0FFH       ; Flag bad write
jp     LastPos

; "?"
; Suspend all communication for 30 seconds
GotRs3F:
clr    RSCOMMAND            ; Throw out any command currently
                                   ; running
jp     NoPos                ; Ignore all RS232 data

"@
Force Up State
GotRs40:
cp     STATE, #DN_DIRECTION   ; If traveling down, make sure that
jr     z, dontup             ; the door autoreverses first
cp     STATE, #AUTO_REV       ; If the door is autoreversing or
jp     z, NoPos              ; at the up limit, don't let the
cp     STATE, #UP_POSITION    ; up direction state be set
jp     z, NoPos              ;
ld     REASON, #00H          ; Set the reason as command
call  SET_UP_DIR_STATE
jp     NoPos

dontup:
ld     REASON, #00H          ; Set the reason as command
call  SET_AREV_STATE         ; Autoreverse the door
jp     NoPos                ;

"A
Force Down State
GotRs41:
cp     STATE, #5h            ; test for the down position
jp     z, NoPos              ;

clr    REASON                ; Set the reason as command
call  SET_DN_DIR_STATE
jp     NoPos

; "B"
; Force Stop State
GotRs42:
clr    REASON                ; Set the reason as command
call  SET_STOP_STATE
jp     NoPos

; "C"
; Force Up Limit State
GotRs43:
clr    REASON                ; Set the reason as command
call  SET_UP_POS_STATE
jp     NoPos

; "D"
; Force Down Limit State
GotRs44:
clr    REASON                ; Set the reason as command
call  SET_DN_POS_STATE
jp     NoPos

```

```

; "E"
; Return min. force during travel
GotRs45:
;   ld    RS232DAT, MIN_RPM_HI           ; Return high and low
;   cp    RS_COUNTER, #090h             ; bytes of min. force read
;   jp    ult, MidPos                    ;
;   ld    RS232DAT, MIN_RPM_LO           ;
;   jp    LastPos                        ;

; "F"
; Leave RS232 mode -- go back to scanning for wall control switches
GotRs46:

;   clr    RsMode                        ; Exit the rs232 mode
;   ld     STATUS, #CHARGE                ; Scan for switches again
;   clr    RS_COUNTER                    ; Wait for input again
;   ld     rscommand, #0FFH              ; turn off command
;   ret

; "G"
; (No Function)
GotRs47:
;   jp     NoPos

; "H"
; 45 Second search for pass point the setup for the door
GotRs48:
;   ld     SKIPRADIO, #0FFH              ; Disable radio EEPROM reads / writes
;   ld     MTEMPH, #0FFH                 ; Erase the up limit and down limit
;   ld     MTEMPL, #0FFH                 ; in EEPROM memory
;   ld     ADDRESS, #UPLIMADDR           ;
;   call   WRITEMEMORY                   ;
;   ld     ADDRESS, #DNLIMADDR           ;
;   call   WRITEMEMORY                   ;
;   ld     UP_LIMIT_HI, #HIGH(SetupPos)  ; Set the door to travel
;   ld     UP_LIMIT_LO, #LOW(SetupPos)   ; to the setup position
;   ld     POSITION_HI, #040H             ; Set the current position to unknown
;   and    PassCounter, #100000000b      ; Reset to activate on first pass point seen
;   call   SET_UP_DIR_STATE              ; Force the door to travel
;   ld     OnePass, STATE                 ; without a limit refresh
;   jp     NoPos

; "I"
; Return radio drop-out timer
GotRs49:
;   clr    RS232DAT                      ; Initially say no radio on
;   cp     RTO, #RDROPTIME                ; If there's no radio on,
;   jp     uge, LastPos                    ; then broadcast that
;   com    RS232DAT                        ; Set data to FF
;   jp     LastPos

; "J"
; Return current position
GotRs4A:
;   ld     RS232DAT, POSITION_HI           ;
;   cp     RS_COUNTER, #090H             ; Test for no words out yet
;   jp     ult, MidPos                    ; If not, transmit high byte
;   ld     RS232DAT, POSITION_LO
;   jp     LastPos

; "K"
; Set radio Received
GotRs4B:
;   cp     L_A_C, #070H                  ; If we were positioning the up limit,

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    jr      ult, NormalRSRadio ; then start the learn cycle
    jr      z, FirstRSLearn    ;
    cp      L_A_C, #071H       ; If we had an error,
    jp      nz, NoPos           ; re-learn, otherwise ignore
ReLearnRS:
    ld      L_A_C, #072H       ; Set the re-learn state
    call    SET_UP_DIR_STATE   ;
    jp      NoPos              ;
FirstRSLearn:
    ld      L_A_C, #073H       ; Set the learn state
    call    SET_UP_POS_STATE   ; Start from the "up limit"
    jp      NoPos              ;
NormalRSRadio:
    clr     LAST_CMD           ; mark the last command as radio
    ld      RADIO_CMD, #0AAH    ; set the radio command
    jp      NoPos              ; return

; "L"
; Direct-connect sensitivity test -- toggle worklight for any code
GotRs4C:
;     clr     RTO               ; Reset the drop-out timer
;     ld      CodeFlag, #SENS_TEST ; Set the flag to test sensitivity
;     jp      NoPos
; "M"
GotRs4D:
;     jp      NoPos
; "N"
; If we are within the first 4 seconds and RS232 mode is not yet enabled,
; then echo the nybble on P30 - P33 on all other nybbles
; (A.K.A. The 6800 test)
GotRs4E:
;     cp      SDISABLE, #32      ; If the 4 second init timer
;     jp      ult, ExitNoTest    ; is done, don't do the test
;
;     di                          ; Shut down all other GDO operations
;     ld      COUNT_HI, #002H    ; Set up to loop for 512 iterations,
;                                ; totaling 13.056 milliseconds
;     clr     COUNT_LO           ;
;     ld      P01M, #00000100b   ; Set all possible pins of micro.
;     ld      P2M, #00000000b    ; to outputs for testing
;     ld      P3M, #00000001b    ;
;     WDT                       ; Kick the dog

TimingLoop:
;     clr     REGTEMP            ; Create a byte of identical nybbles
;     ld      REGTEMP2, P3       ; from P30 - P33 to write to all ports
;     and     REGTEMP2, #00001111b
;     or      REGTEMP, REGTEMP2
;     swap    REGTEMP2
;     or      REGTEMP, REGTEMP2
;     ld      P0, REGTEMP        ; Echo the nybble to all ports
;     ld      P2, REGTEMP
;     ld      P3, REGTEMP
;     decw    COUNT             ; Loop for 512 iterations
;     jr      nz, TimingLoop
;     jp      START             ; When done, reset the system

; "O"
; Return max. force during travel
;
GotRs4F:
;     ld      RS232DAT, P32_MAX_HI ; Return high and low
;     cp      RS_COUNTER, #090h    ; bytes of max. force read
;     jp      ult, MidPos

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```

;      ld      RS232DAT,P32_MAX_LO
;      jp      LastPos

; "P"
; Return the measured temperature range
GotRs50:

      jr      NoPos

; "Q"
; Return address of last memory matching
; radio code received
GotRs51:

;      ld      RS232DAT, RTEMP      ; Send back the last matching address
;      jr      LastPos

; "R"
; Set Rs232 mode -- No ultra board present
; Return Version
GotRs52:
      clr      UltraBrd      ; Clear flag for ultra board present
SetIntoRs232:
      ld      RS232DAT,#VERSIONNUM      ; Initially return the version
      cp      RsMode,#00      ; If this is the first time we're
      jr      ugt, LockedInNoCR      ; locking RS232, signal it
      ld      RS232DAT,#0BBH      ; Return a flag for initial RS232 lock

LockedInNoCR:
      ld      RsMode,#32
      jr      LastPos

; "S"
; Set Rs232 mode -- Ultra board present
; Return Version
GotRs53:

      jr      NoPos

; "T"
; Range test -- toggle worklight whenever a good memory-matching code
; is received
GotRs54:

;      clr      RTO      ; Reset the drop-out timer
;      ld      CodeFlag, #RANGETEST      ; Set the flag to test sensitivity
;      jr      NoPos

; "U"
; (No Function)
GotRs55:

      jr      NoPos

; "V"
; Return current values of up and down force pots
GotRs56:

      ld      RS232DAT,UPFORCE      ; Return values of up and down
      cp      RS_COUNTER,#090h      ; force pots.
      jp      ult,MidPos
      ld      RS232DAT,DNFORCE
      jr      LastPos

MidPos:
      or      RS_COUNTER, #10000000B      ; Set the output mode
      inc     RS_COUNTER      ; Transmit the next byte

```

```

        jr      RSDone                ; exit

LastPos:
        ld      RS_COUNTER, #11110000B        ; set the start flag for last byte
        ld      rscommand, #0FFH              ; Clear the command
        jr      RSDone                    ; Exit

ExitNoTest:
NoPos:
        clr     RS_COUNTER                ; Wait for input again
        ld      rscommand, #0FFH          ; turn off command

RSDone:
        ld      RsMode, #32                ;
        ld      STATUS, #RSSTATUS          ; Set the wall control to RS232
        or      P3, #CHARGE_SW            ; Turn on the pull-ups
        and     P3, #~DIS_SW              ;
        ret

;*****
; Radio interrupt from a edge of the radio signal
;*****
RADIO_INT:
        push    RP                        ; save the radio pair
        srp     #RadioGroup              ; set the register pointer

        ld      rtempH, T0EXT              ; read the upper byte
        ld      rtempL, T0                ; read the lower byte
        tm      IRQ, #00010000B           ; test for pending int
        jr      z, RTIMEOK                 ; if not then ok time
        tm      rtempL, #10000000B        ; test for timer reload
        jr      z, RTIMEOK                 ; if not reloaded then ok
        dec     rtempH                    ; if reloaded then dec high for sync

RTIMEOK:
        clr     R_DEAD_TIME                ; clear the dead time

        .IF     TwoThirtyThree
        and     IMR, #11111110B           ; turn off the radio interrupt
        .ELSE
        and     IMR, #11111100B           ; Turn off the radio interrupt
        .ENDIF

        ld      RTimeDH, RTimePH          ; find the difference
        ld      RTimeDL, RTimePL          ;
        sub     RTimeDL, rtempL            ;
        sbc     RTimeDH, rtempH            ; in past time and the past time in temp

RTIMEDONE:
        tm      P3, #00000100B            ; test the port for the edge
        jr      nz, ACTIVETIME            ; if it was the active time then branch

INACTIVETIME:
        cp      RINFILTER, #0FFH          ; test for active last time
        jr      z, GOINACTIVE             ; if so continue
        jp      RADIO_EXIT                ; if not the return

GOINACTIVE:

        .IF     TwoThirtyThree
        or      IRQ, #01000000B          ; set the bit setting direction to pos edge
        .ENDIF

        clr     RINFILTER                  ; set flag to inactive
        ld      rtimeih, RTimeDH          ; transfer difference to inactive
        ld      rtimeil, RTimeDL          ;
        ld      RTimePH, rtempH           ; transfer temp into the past
        ld      RTimePL, rtempL           ;

        CP      radioc, #01H              ; inactive time after sync bit
        JP      NZ, RADIO_EXIT            ; exit if it was not sync

```

```

TM      RadioMode, #ROLL_MASK      ;If in fixed mode,
JR      z, FixedBlank              ;no number counter exists
CP      rtimeih, #0AH              ;2.56ms for rolling code mode
JP      ULT, RADIO_EXIT             ;pulse ok exit as normal
CLR     radioc                     ;if pulse is longer, bogus sync, restart sync search
JP      RADIO_EXIT                 ; return

FixedBlank:
CP      rtimeih, #014H             ; test for the max width 5.16ms
JP      ULT, RADIO_EXIT             ;pulse ok exit as normal
CLR     radioc                     ;if pulse is longer, bogus sync, restart sync search
;
JP      RADIO_EXIT                 ; return
ACTIVETIME:
CP      RINFILTER, #00H            ; test for active last time
JR      z, GOACTIVE                ; if so continue
JR      RADIO_EXIT                 ; if not the return
GOACTIVE:
;
; .IF TwoThirtyThree
; and IRQ, #00111111B              ; clear bit setting direction to neg edge
; .ENDIF
;
ld      RINFILTER, #0FFH           ;
ld      rtimeah, RTimeDH           ; transfer difference to active
ld      rtimeal, RTimeDL           ;
ld      RTimePH, rtempH            ; transfer temp into the past
ld      RTimePL, rtempL            ;
GotBothEdges:
ei                                     ; enable the interrupts
CP      radioc, #1                 ; test for the blank timing
JP      ugt, INSIG                 ; if not then in the middle of signal
; .IF UseSiminor
; JP      z, CheckSiminor           ; Test for a Siminor tx on the first bit
; .ENDIF
inc     radioc                     ; set the counter to the next number
;
TM      RFlag, #00100000B          ;Has a valid blank time occurred
JR      NZ, BlankSkip
;
CP      RadioTimeOut, #10          ; test for the min 10 ms blank time
JR      ult, ClearJump             ; if not then clear the radio
;
OR      RFlag, #00100000B          ;blank time valid! no need to check
BlankSkip:
CP      rtimeah, #00h              ; test first the min sync
JR      z, JustNoise               ; if high byte 0 then clear the radio
SyncOk:
;
TM      RadioMode, #ROLL_MASK      ;checking sync pulse width, fix or Roll
JR      z, Fixedsync
CP      rtimeah, #09h              ;time for roll 1/2 fixed, 2.3ms
JR      uge, JustNoise
JR      SET1
;
Fixedsync:
CP      rtimeah, #012h             ; test for the max time 4.6mS
JR      uge, JustNoise             ; if not clear
;
SET1:
CLR     PREVFIX                    ;Clear the previous "fixed" bit
CP      rtimeah, SyncThresh         ; test for 1 or three time units
JR      uge, SYNC3FLAG              ; set the sync 3 flag
SYNC1FLAG:
TM      RFlag, #01000000b          ;Was a sync 1 word the last received?
JR      z, SETADCODE                ; if not, then this is an A (or D) code
;
SETBCCODE:
ld      radio3h, radio1h           ;Store the last sync 1 word

```

```

ld    radio3l, radio1l
or    RFlag, #00000110b      ;Set the B/C Code flags
and   RFlag, #11110111b      ;Clear the A/D Code Flag
jr    BCCODE

JustNoise:
CLR   radioc                  ;Edge was noise keep waiting for sync bit
JP    RADIO_EXIT

SETADCODE:

or    RFlag, #00001000b

BCCODE:

or    RFlag, #01000000b      ; set the sync 1 memory flag
clr   radio1h                ; clear the memory
clr   radio1l                ;
clr   COUNT1H                ; clear the memory
clr   COUNT1L                ;
jr    DONESET1               ; do the 2X

SYNC3FLAG:
and   RFlag, #10111111b      ; set the sync 3 memory flag
clr   radio3h                ; clear the memory
clr   radio3l                ;
clr   COUNT3H                ; clear the memory
clr   COUNT3L                ;
clr   ID_B                   ; Clear the ID bits

DONESET1:
RADIO_EXIT:
and   SKIPRADIO, # LOW(~NOINT) ;Re-enable radio ints
pop   rp
iret                             ; done return

ClearJump:
or    P2, #10000000b          ; turn of the flag bit for clear radio
jp    ClearRadio              ; clear the radio signal

    .IF UseSiminor
SimRadio:

tm    rtimeah, #10000000b      ; Test for inactive greater than active
jr    nz, SimBitZero          ; If so, binary zero received

SimBitOne:

scf                                     ; Set the bit
jr    RotateInBit             ;

SimBitZero:

rcf

RotateInBit:

rrc   CodeT0                   ; Shift the new bit into the
rrc   CodeT1                   ; radio word
rrc   CodeT2                   ;
rrc   CodeT3                   ;
rrc   CodeT4                   ;
rrc   CodeT5                   ;

inc   radioc                   ; increase the counter

cp    radioc, #(49 + 128)      ; Test for all 48 bits received
jp    ugt, CLEARRADIO          ;
jp    z, KnowSimCode           ;
jp    RADIO_EXIT               ;

```

```

CheckSiminor:
    tm    RadioMode, #ROLL_MASK        ; If not in a rolling mode,
    jr    z, INSIG                     ; then it can't be a Siminor transmitter
    cp    RadioTimeOut, #35             ; If the blank time is longer than 35 ms,
    jr    ugt, INSIG                   ; then it can't be a Siminor unit

    or    RadioC, #10000000b           ; Set the flag for a Siminor signal
    clr    ID_B                         ; No ID bits for Siminor
.ENDIF

INSIG:
    AND    RFlag, #11011111b           ; clear blank time good flag
    cp    rtimeih, #014h                ; test for the max width 5.16
    jr    uge, ClearJump                ; if too wide clear
    cp    rtimeih, #00h                 ; test for the min width
    jr    z, ClearJump                  ; if high byte is zero, pulse too narrow

ISigOk:
    cp    rtimeah, #014h                ; test for the max width
    jr    uge, ClearJump                ; if too wide clear
    cp    rtimeah, #00h                 ; if greater then 0 then signal ok
    jr    z, ClearJump                  ; if too narrow clear

ASigOk:
    sub    rtimeal, rtimeil              ; find the difference
    sbc    rtimeah, rtimeih

    .IF    UseSiminor

    tm    RadioC, #10000000b           ; If this is a Siminor code,
    jr    nz, SimRadio                 ; then handle it appropriately

    .ENDIF

    tm    rtimeah, #10000000b           ; find out if neg
    jr    nz, NEGDIFF2                 ; use 1 for ABC or D
    jr    POSDIFF2

POSDIFF2:
    cp    rtimeah, BitThresh            ; test for 3/2
    jr    ult, BITIS2                  ; mark as a 2
    jr    BITIS3

NEGDIFF2:
    com    rtimeah                      ; invert
    cp    rtimeah, BitThresh            ; test for 2/1
    jr    ult, BIT2COMP                 ; mark as a 2
    jr    BITIS1

BITIS3:
    ld    RADIOBIT, #2h                 ; set the value
    jr    GOTRADBIT

BIT2COMP:
    com    rtimeah                      ; invert

BITIS2:
    ld    RADIOBIT, #1h                 ; set the value
    jr    GOTRADBIT

BITIS1:
    com    rtimeah                      ; invert
    ld    RADIOBIT, #0h                 ; set the value

GOTRADBIT:
    clr    rtimeah                      ; clear the time
    clr    rtimeal
    clr    rtimeih
    clr    rtimeil

    ;
    ei                                  ; enable int rrupts --REDUNDANT

ADDRADBIT:
    SetRpToRadio2Group                  ; Macro for assembler error
    ;
    srp    #Radio2Group                  ; -- this is what it does
    tm    rflag, #010000000b             ; test for radio 1 / 3
    jr    nz, RC1INC                      ;

RC3INC:
    tm    RadioMode, #ROLL_MASK          ; If in fixed mode,

```



```

        jr      z, Radio3F      ; no number counter exists
        tm      RadioC, #00000001b ; test for even odd number
        jr      nz, COUNT3INC   ; if EVEN number counter

Radio3INC:                                ; else radio

        call    GETTRUEFIX      ;Get the true fixed bit
        cp      RadioC, #14     ; test the radio counter for the specials
        jr      uge, SPECIAL_BITS ; save the special bits seperate

Radio3R:
Radio3F:
        srp     #RadioGroup
        di      ; Disable interrupts to avoid pointer collision
        ld      pointerh, #Radio3H ; get the pointer
        ld      pointerl, #Radio3L ;
        jr      AddAll

SPECIAL_BITS:
        cp      RadioC, #20     ; test for the switch id
        jr      z, SWITCHID     ; if so then branch

        ld      RTempH, id_b     ; save the special bit
        add     id_b, RTempH     ; *3
        add     id_b, RTempH     ; *3
        add     id_b, radiobit   ; add in the new value
        jr      Radio3R

SWITCHID:
        cp      id_b, #18       ; If this was a touch code,
        jr      uge, Radio3R    ; then we already have the ID bit
        ld      sw_b, radiobit  ; save the switch ID
        jr      Radio3R

RC1INC:
        tm      RadioMode, #ROLL_MASK ; If in fixed mode, no number counter
        jr      z, RadiolF
        tm      RadioC, #00000001b ; test for even odd number
        jr      nz, COUNT1INC   ; if odd number counter

RadiolINC:                                ; else radio
        call    GETTRUEFIX      ;Get the real fixed code
        cp      RadioC, #02     ; If this is bit 1 of the lms code,
        jr      nz, RadiolF     ; then see if we need the switch ID bit
        tm      rflag, #00010000b ; If this is the first word received,
        jr      z, SwitchBit1   ; then save the switch bit regardless
        cp      id_b, #18       ; If we have a touch code,
        jr      ult, RadiolF     ; then this is our switch ID bit

SwitchBit1:
        ld      sw_b, radiobit   ; Save touch code ID bit

RadiolF:
        srp     #RadioGroup
        di      ; Disable interrupts to avoid pointer collision
        ld      pointerh, #RadiolH ; get the pointer
        ld      pointerl, #RadiolL ;
        jr      AddAll

GETTRUEFIX:
        ; Chamberlain proprietary fixed code
        ; bit decryption algorithm goes here

        ret

COUNT3INC:
        ld      rollbit, radiobit ; Store the rolling bit
        srp     #RadioGroup
        di      ; Disable interrupts to avoid pointer collision
        ld      pointerh, #COUNT3H ; get the pointer
        ld      pointerl, #COUNT3L ;
        jr      AddAll

COUNT1INC:

```


CounterCorrected:

```
srp    #RadioGroup          ;
clr    RRT0                  ; clear the got a radio flag
tm     SKIPRADIO, #NOECOMM   ; test for the skip flag
jp     nz, CLEARRADIO        ; if skip flag is active then donot look at EE mem
```

NotCode:

```
cp     ID_B, #18              ;If the ID bits total more than 18,
jr     ult, NotCode           ;
or     RFlag, #00000100b      ;then indicate a touch code
```

STORECODE:

```
ld     ADDRESS, #VACATIONADDR ; set the non vol address to the VAC flag
call   READMEMORY             ; read the value
ld     VACFLAG, MTEMPH         ; save into volital
cp     CodeFlag, #REGLEARN     ; test for in learn mode
jp     nz, TESTCODE            ; if out of learn mode then test for matching

tm     RadioMode, #ROLL_MASK   ;If we are in fixed mode,
jr     z, FixedOnly           ;then don't compare the counters
```

CompareCounters:

```
cp     PCounterA, MirrorA      ; Test for counter match to previous
jp     nz, STORENOTMATCH       ; if no match, try again
cp     PCounterB, MirrorB      ; Test for counter match to previous
jp     nz, STORENOTMATCH       ; if no match, try again
cp     PCounterC, MirrorC      ; Test for counter match to previous
jp     nz, STORENOTMATCH       ; if no match, try again
cp     PCounterD, MirrorD      ; Test for counter match to previous
jp     nz, STORENOTMATCH       ; if no match, try again
```

FixedOnly:

```
cp     PRADIO1H, radio1h        ; test for the match
jp     nz, STORENOTMATCH       ; if not a match then loop again
cp     PRADIO1L, radio1l        ; test for the match
jp     nz, STORENOTMATCH       ; if not a match then loop again
cp     PRADIO3H, radio3h        ; test for the match
jp     nz, STORENOTMATCH       ; if not a match then loop again
cp     PRADIO3L, radio3l        ; test for the match
jp     nz, STORENOTMATCH       ; if not a match then loop again

cp     AUXLEARNSW, #116         ; If learn was not from wall control,
jr     ugt, CMDONLY            ; then learn a command only
```

CmdNotOpen:

```
tm     CMD_DEB, #10000000b      ; If the command switch is held,
jr     nz, CmdOrOCS            ; then we are learning command or o/c/s
```

CheckLight:

```
tm     LIGHT_DEB, #10000000b    ; If the light switch and the lock
jp     z, CLEARRADIO2          ; switch are being held,
tm     VAC_DEB, #10000000b      ; then learn a light trans.
jp     z, CLEARRADIO2          ;
```

LearningLight:

```
tm     RadioMode, #ROLL_MASK     ; Only learn a light trans. if we are in
jr     z, CMDONLY                ; the rolling mode.
ld     CodeFlag, #LRNLIGHT ;
ld     BitMask, #01010101b ;
jr     CMDONLY
```

CmdOrOCS:

```
tm     LIGHT_DEB, #10000000b    ; If the light switch isn't being held,
jr     nz, CMDONLY              ; then see if we are learning o/c/s
```

CheckOCS:

```

tm    VAC_DEB, #10000000b ; If the vacation switch isn't held,
jp    z, CLEARADIO2        ; then it must be a normal command
tm    RadioMode, #ROLL_MASK ; Only learn an o/c/s if we are in
jr    z, CMDONLY           ; the rolling mode.
tm    RadioC, #10000000b ; If the bit for siminor is set,
jr    nz, CMDONLY          ; then don't learn as an o/c/s Tx
ld    CodeFlag, #LRNOCS    ; Set flag to learn o/c/s
ld    BitMask, #10101010b ;

```

CMDONLY:

```

call  TESTCODES            ; test the code to see if in memory now
cp    ADDRESS, #0FFH      ; If the code isn't in memory
jr    z, STOREMATCH

```

WriteOverOCS:

```

dec    ADDRESS            ;
jp     READYTOWRITE

```

STOREMATCH:

```

cp    RadioMode, #ROLL_TEST ; If we are not testing a new mode,
jr    ugt, SameRadioMode ; then don't switch

```

```

ld    ADDRESS, #MODEADDR ; Fetch the old radio mode,
call  READMEMORY         ; change only the low order
tm    RadioMode, #ROLL_MASK ; byte, and write in its new value.
jr    nz, SetAsRoll

```

SetAsFixed:

```

ld    RadioMode, #FIXED_MODE ;
call  FixedNums            ; Set the fixed thresholds permanently
jr    WriteMode

```

SetAsRoll:

```

ld    RadioMode, #ROLL_MODE ;
call  RollNums            ; Set the rolling thresholds permanently

```

WriteMode:

```

ld    MTEMPL, RadioMode ;
call  WRITEMEMORY

```

SameRadioMode:

```

tm    RFlag, #00000010B    ; If the flag for the C code is set,
jp    nz, CCODE           ; then set the C Code address
tm    RFlag, #00000100B    ; test for the b code
jr    nz, BCODE           ; if a B code jump

```

ACODE:

```

ld    ADDRESS, #2BH        ; set the address to read the last written
call  READMEMORY          ; read the memory
inc    MTEMPH              ; add 2 to the last written
inc    MTEMPH
tm    RadioMode, #ROLL_MASK ; If the radio is in fixed mode,
jr    z, FixedMem         ; then handle the fixed mode memory

```

RollMem:

```

inc    MTEMPH              ; Add another 2 to the last written
inc    MTEMPH
and    MTEMPH, #11111100B ; Set to a multiple of four
cp    MTEMPH, #1FH        ; test for the last address
jr    ult, GOTAAADDRESS   ; If not the last address jump
jr    AddressZero        ; Address is now zero

```

FixedMem:

```

and    MTEMPH, #11111110B ; set the address on a even number
cp    MTEMPH, #17H        ; test for the last address
jr    ult, GOTAAADDRESS   ; if not the last address jump

```

AddressZero:

```

ld    MTEMPH, #00        ; set the address to 0

```

GOTAAADDRESS:

```

ld    ADDRESS, #2BH        ; set the address to write the last written
ld    RTemp, MTEMPH        ; save the address
LD    MTEMPL, MTEMPH       ; both bytes same

```

```

call WRITEMEMORY          ; write it
ld ADDRESS,rtemp          ; set the address
jr READYTOWRITE           ;

CCODE:
tm RadioMode, #ROLL_MASK  ; If in rolling code mode,
jp nz, CLEARARRADIO       ; then HOW DID WE GET A C CODE?
ld ADDRESS, #01AH         ; Set the C code address
jr READYTOWRITE           ; Store the C code

BCODE:
tm RadioMode, #ROLL_MASK  ; If in fixed mode,
jr z, BFixed              ; handle normal touch code

BRoll:
cp SW_B, #ENTER           ; If the user is trying to learn a key
jp nz, CLEARARRADIO       ; other than enter, THROW IT OUT
ld ADDRESS, #20H          ; Set the address for the rolling touch code
jr READYTOWRITE

BFixed:
cp radio3h, #90H          ; test for the 00 code
jr nz, BCODEOK            ;
cp radio3l, #29H          ; test for the 00 code
jr nz, BCODEOK            ;
jp CLEARARRADIO           ; SKIP MAGIC NUMBER

BCODEOK:
ld ADDRESS, #18H          ; set the address for the B code
READYTOWRITE:
call WRITCODE             ; write the code in radiol and radio3

NOFIXSTORE:
tm RadioMode, #ROLL_MASK  ; If we are in fixed mode,
jr z, NOWRITESTORE        ; then we are done
inc ADDRESS               ; Point to the counter address
ld RadiolH, MirrorA       ; Store the counter into the radio
ld RadiolL, MirrorB       ; for the writcode routine
ld Radio3H, MirrorC       ;
ld Radio3L, MirrorD       ;
call WRITCODE

call SetMask
com BitMask
ld ADDRESS, #RTYPEADDR ; Fetch the radio types
call READMEMORY           ;

tm RFlag, #10000000b      ; Find the proper byte of the type
jr nz, UpByte             ;

LowByte:
and MTEMPL, BitMask       ; Wipe out the proper bits
jr MaskDone               ;

UpByte:
and MTEMPH, BitMask       ;

MaskDone:
com BitMask               ;

cp CodeFlag, #LRNLIGHT ; If we are learning a light
jr z, LearnLight          ; set the appropriate bits
cp CodeFlag, #LRNOCS      ; If we are learning an o/c/s,
jr z, LearnOCS            ; set the appropriate bits

Normal:
clr BitMask               ; Set the proper bits as command
jr BMRReady

LearnLight:
and BitMask, #01010101b ; Set the proper bits as worklight
jr BMRReady              ; Bit mask is ready

LearnOCS:
cp SW_B, #02H             ; If 'open' switch is not being held,
jp nz, CLEARARRADIO2      ; then don't accept the transmitter
and BitMask, #10101010b ; Set the proper bits as open/close/stop

```

```

BMRReady:
    tm    RFlag, #10000000b    ; Find the proper byte of the type
    jr    nz, UpByt2            ;

LowByt2:
    or    MTEMPL, BitMask      ; Write the transmitter type in
    jr    MaskDon2             ;

UpByt2:
    or    MTEMPH, BitMask      ; Write the transmitter type in
    jr    MaskDon2             ;

MaskDon2:
    call  WRITEMEMORY          ; Store the transmitter types

NOWRITESTORE:
    xor    p0, #WORKLIGHT      ; toggle light
    or     ledport, #ledh       ; turn off the LED for program mode
    ld     LIGHT1S, #244        ; turn on the 1 second blink
    ld     LEARN, #0FFH         ; set learnmode timer
    clr    RTO                  ; disallow cmd from learn
    clr    CodeFlag             ; Clear any learning flags
    jp     CLEARRRADIO          ; return

STORENOTMATCH:
    ld     PRADIO1H, radiolh     ; transfer radio into past
    ld     PRADIO1L, radiol1     ;
    ld     PRADIO3H, radio3h     ;
    ld     PRADIO3L, radio3l     ;
    tm     RadioMode, #ROLL_MASK ; If we are in fixed mode,
    jp     z, CLEARRRADIO        ; get the next code
    ld     PCounterA, MirrorA    ; transfer counter into past
    ld     PCounterB, MirrorB    ;
    ld     PCounterC, MirrorC    ;
    ld     PCounterD, MirrorD    ;
    jp     CLEARRRADIO

TESTCODE:
    cp     ID_B, #18             ; If this was a touch code,
    jp     uge, TCReceived       ; handle appropriately

    tm     RFlag, #00000100b     ; If we have received a B code,
    jr     z, AorDCode           ; then check for the learn mode

    cp     ZZWIN, #64            ; Test 0000 learn window
    jr     ugt, AorDCode         ; if out of window no learn

    cp     RadiolH, #90H         ;
    jr     nz, AorDCode          ;
    cp     RadiolL, #29H         ;
    jr     nz, AorDCode          ;

ZZLearn:
    push   RP
    srp    #LEARNEE_GRP
    call   SETLEARN
    pop    RP
    jp     CLEARRRADIO

AorDCode:
    cp     L_A_C, #070H          ; Test for in learn limits mode
    jr     uge, FS1              ; If so, don't blink the LED
    cp     FAULTFLAG, #0FFH      ; test for a active fault
    jr     z, FS1                ; if a avtive fault skip led set and reset
    and    ledport, #led1        ; turn on the LED for flashing from signal

FS1:
    call   TESTCODES             ; test the codes
    cp     L_A_C, #070H          ; Test for in learn limits mode
    jr     uge, FS2              ; If so, don't blink the LED
    cp     FAULTFLAG, #0FFH      ; test for a active fault
    jr     z, FS2                ; if a avtive fault skip led set and reset
    or     ledport, #ledh        ; turn off the LED for flashing from signal

FS2:

```

```

cp    ADDRESS, #0FFF      ; test for the not matching state
jr    nz, GOTMATCH        ; if matching the send a command if needed
jp    CLEARRRADIO         ; clear the radio

```

SimRollCheck:

```

inc    ADDRESS            ; Point to the rolling code
                                ; (Note: High word always zero)
inc    ADDRESS            ; Point to rest of the counter
call   READMEMORY         ; Fetch lower word of counter
ld     CounterC, MTEMPH    ;
ld     CounterD, MEMPL     ;

cp     CodeT2, CounterC    ; If the two counters are equal,
jr     nz, UpdateSCode    ; then don't activate
cp     CodeT3, CounterD    ;
jr     nz, UpdateSCode    ;
jp     CLEARRRADIO        ; Counters equal -- throw it out

```

UpdateSCode:

```

ld     MTEMPH, CodeT2      ; Always update the counter if the
ld     MEMPL, CodeT3      ; fixed portions match
call   WRITEMEMORY        ;

sub     CodeT3, CounterD   ; Compare the two codes
sbc     CodeT2, CounterC   ;

tm     CodeT2, #10000000b  ; If the result is negative,
jp     nz, CLEARRRADIO    ; then don't activate
jp     MatchGoodSim       ; Match good -- handle normally

```

GOTMATCH:

```

tm     RadioMode, #ROLL_MASK ; If we are in fixed mode,
jr     z, MatchGood2        ; then the match is already valid

tm     RadioC, #10000000b    ; If this was a Siminor transmitter,
jr     nz, SimRollCheck     ; then test the roll in its own way

tm     BitMask, #10101010b  ; If this was NOT an open/close/stop trans,
jr     z, RollCheckB        ; then we must check the rolling value

cp     SW_B, #02             ; If the o/c/s had a key other than '2'
jr     nz, MatchGoodOCS     ; then don't check / update the roll

```

RollCheckB:

```

call   TestCounter        ; Rolling mode -- compare the counter values
cp     CMP, #EQUAL         ; If the code is equal,
jp     z, NOTNEWMATCH     ; then just keep it
cp     CMP, #FWDWIN        ; If we are not in forward window,
jp     nz, CheckPast      ; then forget the code

```

MatchGood:

```

ld     RadiolH, MirrorA    ; Store the counter into memory
ld     RadiolL, MirrorB    ; to keep the roll current
ld     Radio3H, MirrorC    ;
ld     Radio3L, MirrorD    ;
dec     ADDRESS            ; Line up the address for writing
call   WRITECODE           ;

```

MatchGoodOCS:

MatchGoodSim:

```

or     RFlag, #00000001B   ; set the flag for recieving without error
cp     RTO, #RDROPTIME     ; test for the timer time out
jp     ult, NOTNEWMATCH    ; if the timer is active then donot reissue cmd

cp     ADDRESS, #23H       ; If the code was the rolling touch code,
jr     z, MatchGood2      ; then we already know the transmitter type

```

```

call SetMask ; Set the mask bits properly
ld ADDRESS, #RTYPEADDR ; Fetch the transmitter config. bits
call READMEMORY ;
tm RFlag, #10000000b ; If we are in the upper word,
jr nz, UpperD ; check the upper transmitters

LowerD:
and BitMask, MEMPL ; Isolate our transmitter
jr TransType ; Check out transmitter type

UpperD:
and BitMask, MEMPLH ; Isolate our transmitter

TransType:
tm BitMask, #01010101b ; Test for light transmitter
jr nz, LightTrans ; Execute light transmitter
tm BitMask, #10101010b ; Test for Open/Close/Stop Transmitter
jr nz, OCSTrans ; Execute open/close/stop transmitter
; Otherwise, standard command transmitter

MatchGood2:
or RFlag, #00000001b ; set the flag for receiving without error
cp RTO, #RDROPTIME ; test for the timer time out
jp ult, NOTNEWMATCH ; if the timer is active then donot reissue cmd

TESTVAC:
cp VACFLAG, #00B ; test for the vacation mode
jp z, TSTSDISABLE ; if not in vacation mode test the system disable

tm RadioMode, #ROLL_MASK ;
jr z, FixedB

cp ADDRESS, #23H ; If this was a touch code,
jp nz, NOTNEWMATCH ; then do a command
jp TSTSDISABLE ;

FixedB:
cp ADDRESS, #19H ; test for the B code
jp nz, NOTNEWMATCH ; if not a B not a match

TSTSDISABLE:
cp SDISABLE, #32 ; test for 4 second
jp ult, NOTNEWMATCH ; if 6 s not up not a new code
clr RTO ; clear the radio timeout
cp ONEF2, #00 ; test for the 1.2 second time out
jp nz, NOTNEWMATCH ; if the timer is active then skip the command

RADIOCOMMAND:
clr RTO ; clear the radio timeout
tm RFlag, #00000100b ; test for a B code
jr z, BDONTSET ; if not a b code donot set flag

zzwinclr:
clr ZZWIN ; flag got matching B code

BDONTSET:
ld CodeFlag, #BRECEIVED ; flag for aobs bypass

cp L_A_C, #070H ; If we were positioning the up limit,
jr ult, NormalRadio ; then start the learn cycle
jr z, FirstLearn ;
cp L_A_C, #071H ; If we had an error,
jp nz, CLEARRRADIO ; re-learn, otherwise ignore

ReLearning:
ld L_A_C, #072H ; Set the re-learn state
call SET_UP_DIR_STATE ;
jp CLEARRRADIO ;

FirstLearn:
ld L_A_C, #073H ; Set the learn state
call SET_UP_POS_STATE ; Start from the "up limit"
jp CLEARRRADIO ;

NormalRadio:
clr LAST_CMD ; mark the last command as radio

```



```

ld    RADIO_CMD, #0AAH          ; set the radio command
jp    CLEARRADIO                ; return

LightTrans:
clr    RTO                      ; Clear the radio timeout
cp     ONEP2, #00                ; Test for the 1.2 sec. time out
jp     nz, NOTNEWMATCH          ; If it isn't timed out, leave
ld     SW_DATA, #LIGHT_SW       ; Set a light command
jp     CLEARRADIO              ; return

OCSTrans:
cp     SDISABLE, #32            ; Test for 4 second system disable
jp     ult, NOTNEWMATCH         ; if not done not a new code
cp     VACFLAG, #00H            ; If we are in vacation mode,
jp     nz, NOTNEWMATCH         ; don't obey the transmitter
clr    RTO                      ; Clear the radio timeout
cp     ONEP2, #00                ; test for the 1.2 second timeout
jp     nz, NOTNEWMATCH         ; If the timer is active the skip command

cp     SW_B, #02                ; If the open button is pressed,
jr     nz, CloseOrStop         ; then process it

OpenButton:
cp     STATE, #STOP             ; If we are stopped or
jr     z, OpenUp               ; at the down limit, then
cp     STATE, #DN_POSITION      ; begin to move up
jr     z, OpenUp               ;
cp     STATE, #DN_DIRECTION     ; If we are moving down,
jr     nz, OCSExit             ; then autoreverse
ld     REASON, #010H           ; Set the reason as radio
call   SET_AREV_STATE          ;
jr     OCSExit                 ;

OpenUp:
ld     REASON, #010H           ; Set the reason as radio
call   SET_UP_DIR_STATE        ;

OCSExit:
jp     CLEARRADIO              ;

CloseOrStop:
cp     SW_B, #01                ; If the stop button is pressed,
jr     nz, CloseButton         ; then process it

StopButton:
cp     STATE, #UP_DIRECTION     ; If we are moving or in
jr     z, StopIt               ; the autoreverse state,
cp     STATE, #DN_DIRECTION     ; then stop the door
jr     z, StopIt               ;
cp     STATE, #AUTO_REV         ;
jr     z, StopIt               ;
jr     OCSExit                 ;

StopIt:
ld     REASON, #010H           ; Set the reason as radio
call   SET_STOP_STATE          ;
jr     OCSExit                 ;

CloseButton:
cp     STATE, #UP_POSITION      ; If we are at the up limit
jr     z, CloseIt              ; or stopped in travel,
cp     STATE, #STOP             ; then send the door down
jr     z, CloseIt              ;
jr     OCSExit                 ;

```

CloseIt:

```
ld    REASON, #010H      ; Set the reason as radio
call  SET_DN_DIR_STATE
jr    OCSExit
```

SetMask:

```
and    RFlag, #01111111b      ; Reset the page 1 bit
tm     ADDRESS, #111100C0b ; If our address is on page 1,
jr     z, InLowerByte          ; then set the proper flag
or     RFlag, #10000000b      ;
```

InLowerByte:

```
tm     ADDRESS, #00001000b ; Binary search to set the
jr     z, ZeroOrFour          ; proper bits in the bit mask
```

EightOrTwelve:

```
ld     BitMask, #11110000b
jr     LSNybble
```

ZeroOrFour:

```
ld     BitMask, #00001111b ;
```

LSNybble:

```
tm     ADDRESS, #00000100b
jr     z, ZeroOrEight
```

FourOrTwelve:

```
and    BitMask, #11001100b ;
ret
```

ZeroOrEight:

```
and    BitMask, #00110011b ;
ret
```

TESTCODES:

```
ld     ADDRESS, #RTYPEADDR ; Get the radio types
call   READMEMORY           ;
ld     RadioTypes, MTEMPL   ;
ld     RTypes2, MTEMPH      ;
tm     RadioMode, #ROLL_MASK ;
jr     nz, RollCheck        ;
clr    RadioTypes           ;
clr    RTypes2              ;
```

RollCheck:

```
clr    ADDRESS              ; start address is 0
```

NEXTCODE:

```
call   SetMask              ; Get the appropriate bit mask
and    BitMask, RadioTypes ; Isolate the current transmitter types
```

HAVEMASK:

```
call   READMEMORY           ; read the word at this address
cp     MTEMPH, radio1h      ; test for the match
jr     nz, NOMATCH          ; if not matching then do next address
cp     MTEMPL, radio1l      ; test for the match
jr     nz, NOMATCH          ; if not matching then do next address
inc    ADDRESS              ; set the second half of the code
call   READMEMORY           ; read the word at this address
tm     BitMask, #10101010b ; If this is an Open/Close/Stop trans.,
jr     nz, CheckOCS1        ; then do the different check
cp     CodeFlag, #LRNOCS    ; If we are in open/close/stop learn mode,
jr     z, CheckOCS1         ; then do the different check
cp     MTEMPH, radio3h      ; test for the match
jr     nz, NOMATCH2         ; if not matching then do the next address
cp     MTEMPL, radio3l      ; test for the match
jr     nz, NOMATCH2         ; if not matching then do the next address

ret                                ; return with the address of the match
```

CheckOCS1:

```
sub    MTEMPL, radio3l      ; Subtract the radio from the memory
sbc    MTEMPH, radio3h      ;
cp     CodeFlag, #LRNOCS    ; If we are trying to learn open/close/stop,
jr     nz, Positive         ; then we must complement to be positive
```

```

com    MTEMPL          ;
com    MTEMPH          ;
add    MTEMPL, #1      ; Switch from ones complement to 2's
adc    MTEMPH, #0      ; complement

Positive:
cp      MTEMPH, #00     ; We must be within 2 to match properly
jr      nz, NOMATCH2   ;
cp      MTEMPL, #02     ;
jr      ugt, NOMATCH2  ;

ret                                ; Return with the address of the match

NOMATCH:
inc     ADDRESS          ; set the address to the next code

NOMATCH2:
inc     ADDRESS          ; set the address to the next code
tm      RadioMode, #ROLL_MASK ; If we are in fixed mode,
jr      z, AtNextAdd    ; then we are at the next address
inc     ADDRESS          ; Roll mode -- advance past the counter
inc     ADDRESS          ;
cp      ADDRESS, #10H    ; If we are on the second page
jr      nz, AtNextAdd    ; then get the other tx. types
ld      RadioTypes, RTypes2 ;

AtNextAdd:
cp      ADDRESS, #22H    ; test for the last address
jr      ult, NEXTCODE    ; if not the last address then try again

GOTNOMATCH:
ld      ADDRESS, #0FFH   ; set the no match flag
ret                                ; and return

NOTNEWMATCH:
clr     RTO              ; reset the radio time out
and     RFlag, #00000001B ; clear radio flags leaving recieving w/o error
clr     radioc           ; clear the radio bit counter
ld      LEARNT, #0FFH    ; set the learn timer "turn off" and backup
jp      RADIO_EXIT       ; return

CheckPast:
; Proprietary algorithm for maintaining
; rolling code counter
; Jumps to either MatchGood, UpdatePast or CLEARRADIO

UpdatePast:
ld      LastMatch, ADDRESS ; Store the last fixed code received
ld      PCounterA, MirrorA ; Store the last counter received
ld      PCounterB, MirrorB ;
ld      PCounterC, MirrorC ;
ld      PCounterD, MirrorD ;

CLEARRADIO2:
ld      LEARNT, #0FFH     ; Turn off the learn mode timer
clr     CodeFlag

CLEARRADIO:
; IF      TwoThirtyThree
and     IRQ, #00111111B   ; clear the bit setting direction to neg edge
; ENDIF

ld      RINFILTER, #0FFH   ; set flag to active

CLEARRADIOA:
tm      RFlag, #00000001B ; test for receiving without error
jr      z, SKIPRTO        ; if flag not set then donot clear timer
clr     RTO               ; clear radio timer

SKIPRTO:
clr     radioc            ; clear the radio counter
clr     RFlag             ; clear the radio flag

```

```

;      clr      ID_B          ; Cl ar the ID bits
      jp      RADIO_EXIT      ; return

```

TCReceived:

```

      cp      L_A_C, #070H      ; Test for in learn limits mode
      jr      uge, TestTruncate ; If so, don't blink the LED
      cp      FAULTFLAG, #0FFH  ; If no fault
      jr      z, TestTruncate   ; turn on the led
      and     ledport, #ledl     ;
      jr      TestTruncate      ; Truncate off most significant digit

```

TruncTC:

```

      sub     RadiolL, #0E3h      ; Subtract out 3^9 to truncate
      sbc     RadiolH, #04Ch      ;

```

TestTruncate:

```

      cp      RadiolH, #04Ch      ; If we are greater than 3^9,
      jr      ugt, TruncTC        ; truncate down
      jr      ult, GotTC          ;
      cp      RadiolL, #0E3h      ;
      jr      uge, TruncTC        ;

```

GotTC:

```

      ld      ADDRESS, #TOUCHID    ; Check to make sure the ID code is good
      call    READMEMORY           ;
      cp      L_A_C, #070H      ; Test for in learn limits mode
      jr      uge, CheckID       ; If so, don't blink the LED
      cp      FAULTFLAG, #0FFH  ; If no fault,
      jr      z, CheckID         ; turn off the LED
      or      ledport, #ledh      ;

```

CheckID:

```

      cp      MTEMPH, Radio3H      ;
      jr      nz, CLEARRRADIO      ;
      cp      MTEMPL, Radio3L      ;
      jr      nz, CLEARRRADIO      ;

      call    TestCounter          ; Test the rolling code counter
      cp      CMP, #EQUAL          ; If the counter is equal,
      jp      z, NOTNEWMATCH       ; then call it the same code
      cp      CMP, #FWDWIN        ;
      jr      nz, CLEARRRADIO      ;

```

; Counter good -- update it

```

      ld      COUNT1H, RadiolH      ; Back up radio code
      ld      COUNT1L, RadiolL      ;

      ld      RadiolH, MirrorA      ; Write the counter
      ld      RadiolL, MirrorB      ;
      ld      Radio3H, MirrorC      ;
      ld      Radio3L, MirrorD      ;
      dec     ADDRESS              ;
      call    WRITECODE            ;

      ld      RadiolH, COUNT1H      ; Restore the radio code
      ld      RadiolL, COUNT1L      ;

      cp      CodeFlag, #NORMAL    ; Find and jump to current mode
      jr      z, NormTC            ;
      cp      CodeFlag, #LRNTEMP   ;
      jp      z, LearnTMP          ;
      cp      CodeFlag, #LRNDURTN  ;
      jp      z, LearnDur          ;
      jp      CLEARRRADIO          ;

```

NormTC:

```
ld    ADDRESS, #TOUCHPERM ; Compare the four-digit touch
call  READMEMORY           ; code to our permanent password
cp    RadiolH, MTEMPH      ;
jr    nz, CheckTCTemp      ;
cp    RadiolL, MEMPL       ;
jr    nz, CheckTCTemp      ;

cp    SW_B, #ENTER         ; If the ENTER key was pressed,
jp    z, RADIOCOMMAND      ; issue a B code radio command
cp    SW_B, #POUND         ; If the user pressed the pound key,
jr    z, TCLearn           ; enter the learn mode
; Star key pressed -- start 30 s timer

clr    LEARNT              ;
ld    FLASH_COUNTER, #06h ; Blink the worklight three
ld    FLASH_DELAY, #FLASH_TIME ; times quickly
ld    FLASH_FLAG, #OFFH    ;
ld    CodeFlag, #LRNTEMP   ; Enter learn temporary mode
jp    CLEARRADIO           ;
```

Clearn:

```
ld    FLASH_COUNTER, #04h ; Blink the worklight two
ld    FLASH_DELAY, #FLASH_TIME ; times quickly
ld    FLASH_FLAG, #OFFH    ;

push  RP                   ; Enter learn mode
srp   #LEARNEE_GRP
call  SETLEARN
pop   RP

jp    CLEARRADIO
```

CheckTCTemp:

```
ld    ADDRESS, #TOUCHTEMP ; Compare the four-digit touch
call  READMEMORY           ; code to our temporary password
cp    RadiolH, MTEMPH      ;
jp    nz, CLEARRADIO       ;
cp    RadiolL, MEMPL       ;
jp    nz, CLEARRADIO       ;

cp    STATE, #DN_POSITION ; If we are not at the down limit,
jp    nz, RADIOCOMMAND      ; issue a command regardless

ld    ADDRESS, #DURAT      ; If the duration is at zero,
call  READMEMORY           ; then don't issue a command
cp    MEMPL, #00           ;
jp    z, CLEARRADIO        ;

cp    MTEMPH, #ACTIVATIONS ; If we are in number of activations
jp    nz, RADIOCOMMAND      ; mode, then decrement the
dec   MEMPL               ; number of activations left
call  WRITEMEMORY         ;
jp    RADIOCOMMAND
```

LearnTMP:

```
cp    SW_B, #ENTER         ; If the user pressed a key other
jp    nz, CLEARRADIO       ; then enter, reject the code

ld    ADDRESS, #TOUCHPERM ; If the code entered matches the
call  READMEMORY           ; permanent touch code,
cp    RadiolH, MTEMPH      ; then reject the code as a
jp    nz, TempGood         ; temporary code
cp    RadiolL, MEMPL       ;
jp    z, CLEARRADIO        ;
```

TempGood:

```
ld    ADDRESS, #TOUCHTEMP ; Write the code into temp.
ld    MTEMPH, RadiolH      ; code memory
ld    MTEMPL, RadiolL      ;
call  WRITEMEMORY          ;
```

```
ld    FLASH_COUNTER, #08h ; Blink the worklight four
ld    FLASH_DELAY, #FLASH_TIME ; times quickly
ld    FLASH_FLAG, #OFFH    ;
```

; Start 30 s timer

```
clr    LEARNT
ld    CodeFlag, #LRNDURTN ; Enter learn duration mode
jp     CLEARRADIO          ;
```

LearnDur:

```
cp     RadiolH, #00        ; If the duration was > 255,
jp     nz, CLEARRADIO      ; reject the duration entered
```

```
cp     SW_B, #POUND        ; If the user pressed the pound
jr     z, NumDuration      ; key, number of activations mode
cp     SW_B, #STAR         ; If the star key was pressed,
jr     z, HoursDur         ; enter the timer mode
jp     CLEARRADIO          ; Enter pressed -- reject code
```

NumDuration:

```
ld     MTEMPH, #ACTIVATIONS ; Flag number of activations mode
jr     DurationIn          ;
```

HoursDur:

```
ld     MTEMPH, #HOURS      ; Flag number of hours mode
```

DurationIn:

```
ld     MTEMPL, RadiolL     ; Load in duration
ld     ADDRESS, #DURAT     ; Write duration and mode
call  WRITEMEMORY          ; into nonvolatile memory
```

```
; Give worklight one long blink
xor    P0, #WORKLIGHT      ; Give the light one blink
ld     LIGHT1S, #244       ; lasting one second
clr    CodeFlag            ; Clear the learn flag
jp     CLEARRADIO
```

```
-----
;   Test Rolling Code Counter Subroutine
;   Note: CounterA-D will be used as temp registers
;   -----
```

TestCounter:

```
push   RP
srp     #CounterGroup
inc     ADDRESS             ; Point to the rolling code counter
call    READMEMORY         ; Fetch lower word of counter
ld      countera, MTEMPH
ld      counterb, MEMPL
inc     ADDRESS             ; Point to rest of the counter
call    READMEMORY         ; Fetch upper word of counter
ld      counterc, MTEMPH
ld      counterd, MEMPL
```

```
-----
;   Subtract old counter (countera-d) from current
```

```
; counter (mirrora-d) and store in counter-a-d
```

```
-----
com  countera          ; Obtain twos complement of counter
com  counterb
com  counterc
com  counterd
add  counterd, #01H
adc  counterc, #00H
adc  counterb, #00H
adc  countera, #00H

add  counterd, mirrord  ; Subtract
adc  counterc, mirrorc
adc  counterb, mirrorb
adc  countera, mirrora
```

```
-----
; If the msb of counterd is negative, check to see
; if we are inside the negative window
-----
```

```
tm  counterd, #10000000B
jr  z, CheckFwdWin
```

CheckBackWin:

```
cp  countera, #0FFH      ; Check to see if we are
jr  nz, OutOfWindow      ; less than -0400H
cp  counterb, #0FFH      ; (i.e. are we greater than
jr  nz, OutOfWindow      ; 0xFFFFFC00H)
cp  counterc, #0FCH      ;
jr  ult, OutOfWindow      ;
```

InBackWin:

```
ld  CMP, #BACKWIN      ; Return in back window
jr  CompDone
```

CheckFwdWin:

```
cp  countera, #00H      ; Check to see if we are less
jr  nz, OutOfWindow      ; than 0C00 (3072 = 1024
cp  counterb, #0CH       ; activations)
jr  nz, OutOfWindow
cp  counterc, #0CH       ;
jr  uge, OutOfWindow

cp  counterd, #00H
jr  nz, InFwdWin
cp  counterd, #00H
jr  nz, InFwdWin
```

CountersEqual:

```
ld  CMP, #EQUAL          ; Return equal counters
jr  CompDone
```

InFwdWin:

```
ld  CMP, #FWDWIN        ; Return in forward window
jr  CompDone
```

OutOfWindow:

```
ld  CMP, #OUTOFWIN      ; Return out of any window
```

CompDone:

```

        pop    RP
        ret

;*****
; Clear interrupt
;*****
ClearRadio:

        cp     RadioMode, #ROLL_TEST          ;If in fixed or rolling mode,
        jr     ugt, MODEDONE                  ; then we cannot switch

        tm     T125MS, #000000001b           ;If our 'coin toss' was a zero,
        jr     z, SETROLL                     ; set as the rolling mode

SETFIXED:

        ld     RadioMode, #FIXED_TEST
        call   FixedNums
        jp     MODEDONE

SETROLL:

        ld     RadioMode, #ROLL_TEST
        call   RollNums

MODEDONE:

        clr    RadioTimeOut                   ; clear radio timer
        clr    RadioC                         ; clear the radio counter
        clr    RFlag                          ; clear the radio flags

RRETURN:

        pop    RP                            ; reset the RP
        iret                                  ; return

FixedNums:

        ld     BitThresh, #FIXTHR
        ld     SyncThresh, #FIXSYNC
        ld     MaxBits, #FIXBITS
        ret

RollNums:

        ld     BitThresh, #DTHR
        ld     SyncThresh, #DSYNC
        ld     MaxBits, #DBITS
        ret

```

```

;*****
; rotate mirror LoopCount * 2 then add
;*****

```

```

RotateMirrorAdd:

        rcf                                  ; clear the carry
        rlc    mirrord                       ;
        rlc    mirrorc                       ;
        rlc    mirrorb                       ;
        rlc    mirrora                       ;
        djnz   loopcount, RotateMirrorAdd    ; loop till done

```

```

;*****
; Add mirror to counter
;*****
AddMirrorToCounter:

```



```

add    count rd,mirrord      ;
adc    count rc,mirrorc      ;
adc    count rb,mirrorb      ;
adc    countera,mirrora      ;
ret

;*****
; LEARN DEBOUNCES THE LEARN SWITCH 80ms
; TIMES OUT THE LEARN MODE 30 SECONDS
; DEBOUNCES THE LEARN SWITCH FOR ERASE 6 SECONDS
;*****
LEARN:
    srp    #LEARNEE_GRP      ; set the register pointer
    cp     STATE,#DN_POSITION ; test for motor stoped
    jr     z,TESTLEARN        ;
    cp     STATE,#UP_POSITION ; test for motor stoped
    jr     z,TESTLEARN        ;
    cp     STATE,#STOP        ; test for motor stoped
    jr     z,TESTLEARN        ;
    cp     L_A_C,#074H        ; Test for traveling
    jr     z,TESTLEARN        ;
    ld     learnt,#0FFH       ; set the learn timer
    cp     learnt,#240        ; test for the learn 30 second timeout
    jr     nz,ERASETEST       ; if not then test erase
    jr     learnoff           ; if 30 seconds then turn off the learn mode

TESTLEARN:
    cp     learndb,#236       ; test for the debounced release
    jr     nz,LEARNNOTRELEASED ; if debouncer not released then jump

LEARNNOTRELEASED:
SmartRelease:
    cp     L_A_C, #070H       ; Test for in learn limits mode
    jr     nz, NormLearnBreak ; If not, treat the break as normal

    ld     REASON, #00H       ; Set the reason as command
    call   SET_STOP_STATE    ;

NormLearnBreak:
    clr    LEARNDB           ; clear the debouncer

    ret                     ; return

LEARNNOTRELEASED:
    cp     CodeFlag,#LRNTEMP   ;test for learn mode
    jr     uge,INLEARN         ; if in learn jump
    cp     learndb,#20         ; test for debounce period
    jr     nz,ERASETEST        ; if not then test the erase period

SETLEARN:
    call   SmartSet           ;

ERASETEST:
    cp     L_A_C, #070H       ; Test for in learn limits mode
    jr     uge,ERASERELEASE    ; If so, DON'T ERASE THE MEMORY
    cp     learndb,#0FFH       ; test for learn button active
    jr     nz,ERASERELEASE     ; if button released set the erase timer
    cp     eraset,#0FFH        ; test for timer active
    jr     nz,ERASETIMING      ; if the timer active jump
    clr    eraset             ; clear the erase timer

ERASETIMING:
    cp     eraset,#48         ; test for the erase period
    jr     z,ERASETIME        ; if timed out the erase
    ret                       ; else we return

ERASETIME:
    or     ledport,#ledh      ; turn off the led
    ld     skipradio,#NOLECOMM ; set the flag to skip the radio read
    call   CLEARCODES         ; clear all codes in memory
    clr    skipradio          ; reset the flag to skip radio

    ld     learnt,#0FFH       ; set the learn timer

```

```

        clr    CodeFlag
        ret                                ; return

SmartSet:
        cp     L_A_C, #070H                ; Test for in learn limits mode
        jr     nz, NormLearnMake1          ; If not, treat normally
        ld     REASON, #00H                ; Set the reason as command
        call   SET_DN_NOBLINK
        jr     LearnMakeDone
NormLearnMake1:
        cp     L_A_C, #074H                ; Test for traveling down
        jr     nz, NormLearnMake2          ; If not, treat normally
        ld     L_A_C, #075H                ; Reverse off false floor
        ld     REASON, #00H                ; Set the reason as command
        call   SET_AREV_STATE
        jr     LearnMakeDone
NormLearnMake2:
        clr    LEARNT                      ; clear the learn timer
        ld     CodeFlag, #REGLEARN         ; Set the learn flag
        and    ledport, #led1              ; turn on the led
        clr    VACFLAG                     ; clear vacation mode
        ld     ADDRESS, #VACATIONADDR      ; set the non vol address for vacation
        clr    MTEMPH                      ; clear the data for cleared vacation
        clr    MTEMPL
        ld     SKIPRADIO, #NOEECOMM        ; set the flag
        call   WRITEMEMORY                 ; write the memory
        clr    SKIPRADIO                   ; clear the flag
LearnMakeDone:
        ld     LEARNDB, #0FFH              ; set the debouncer
        ret

ERASERELEASE:
        ld     eraset, #0FFH               ; turn off the erase timer
        cp     learndb, #236               ; test for the debounced release
        jr     z, LEARNRELEASED            ; if debouncer not released then jump
        ret                                ; return

INLEARN:
        cp     learndb, #20                ; test for the debounce period
        jr     nz, TESTLEARNTIMER          ; if not then test the learn timer for time out
        ld     learndb, #0FFH              ; set the learn db
TESTLEARNTIMER:
        cp     learnt, #240                ; test for the learn 30 second timeout
        jr     nz, ERASETEST               ; if not then test erase
learnoff:
        or     ledport, #ledh              ; turn off the led
        ld     learnt, #0FFH               ; set the learn timer
        ld     learndb, #0FFH              ; set the learn debounce
        clr    CodeFlag                    ; Clear ANY code types
        jr     ERASETEST                   ; test the erase timer

;*****
; WRITE WORD TO MEMORY
; ADDRESS IS SET IN REG ADDRESS
; DATA IS IN REG MTEMPH AND MTEMPL
; RETURN ADDRESS IS UNCHANGED
;*****
WRITEMEMORY:
        push   RP                          ; SAVE THE RP
        srp    #LEARNEE_GRP                ; set the register pointer

        call   STARTB                      ; output the start bit
        ld     serial, #00110000B          ; set byte to enable write
        call   SERIALOUT                   ; output the byte
        and    csport, #cs1                ; reset the chip select
        call   STARTB                      ; output the start bit
        ld     serial, #01000000B          ; set the byte for write

```

```

or      s rial,address          ; or in the address
call    SERIALOUT              ; output th byt
ld      serial,mtempH          ; set the first byte to write
call    SERIALOUT              ; output the byte
ld      serial,mtempl          ; set the second byte to write
call    SERIALOUT              ; output the byte
call    ENDWRITE               ; wait for the ready status
call    STARTB                 ; output the start bit
ld      serial,#00000000B      ; set byte to disable write
call    SERIALOUT              ; output the byte
and      csport,#cs1           ; reset the chip select
or      P2M_SHADOW,#clockh     ; Change program switch back to read
ld      P2M,P2M_SHADOW         ;
pop      RP                    ; reset the RP
ret

```

```

;*****
; READ WORD FROM MEMORY
; ADDRESS IS SET IN REG ADDRESS
; DATA IS RETURNED IN REG MTEMPH AND MTEMPL
; ADDRESS IS UNCHANGED
;*****

```

READMEMORY:

```

push    RP                    ;
srp      #LEARNEE_GRP         ; set the register pointer

call    STARTB                ; output the start bit
ld      serial,#10000000B      ; preamble for read
or      serial,address        ; or in the address
call    SERIALOUT              ; output the byte
call    SERIALIN               ; read the first byte
ld      mtempH,serial          ; save the value in mtempH
call    SERIALIN               ; read teh second byte
ld      mtempl,serial          ; save the value in mtempl
and      csport,#cs1           ; reset the chip select
or      P2M_SHADOW,#clockh     ; Change program switch back to read
ld      P2M,P2M_SHADOW         ;
pop      RP                    ;
ret

```

```

;*****
; WRITE CODE TO 2 MEMORY ADDRESS
; CODE IS IN RADIO1H RADIO1L RADIO3H RADIO3L
;*****

```

WRITECODE:

```

push    RP                    ;
srp      #LEARNEE_GRP         ; set the register pointer
ld      mtempH,Radio1H         ; transfer the data from radio 1 to the temps
ld      mtempl,Radio1L         ;
call    WRITEMEMORY           ; write the temp bits
inc      address               ; next address
ld      mtempH,Radio3H         ; transfer the data from radio 3 to the temps
ld      mtempl,Radio3L         ;
call    WRITEMEMORY           ; write the temps
pop      RP                    ;
ret                          ; return

```

```

;*****
; CLEAR ALL RADIO CODES IN THE MEMORY
;*****

```

CLEARCODES:

```

push    RP                    ;
srp      #LEARNEE_GRP         ; set the register pointer
ld      MTEMPH,#OFFH           ; set the codes to illegal codes
ld      MTEMPL,#OFFH           ;
ld      address,#00H           ; clear address 0

```

CLEARC:

```

call    WRITEMEMORY          ; "A0"
inc     address              ; set the next address
cp      address,#(AddressCounter - 1) ; test for the last address of radio
jr      ult,CLEARC
clr     mtemph               ; clear data
clr     mtempl
call    WRITEMEMORY          ; Clear radio types
ld      address,#AddressAPointer ; clear address F
call    WRITEMEMORY          ;

ld      address,#MODEADDR     ;Set EEPROM memory as fixed test
call    WRITEMEMORY          ;

ld      RadioMode, #FIXED_TEST ;Revert to fixed mode testing
ld      BitThresh, #FIXTHR
ld      SyncThresh, #FIXSYNC
ld      MaxBits, #FIXBITS

```

CodesCleared:

```

pop     RP                   ;
ret     ; return

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SERIALOUTLOOP:

```

    rlc    serial                ; get the bit to output into the carry
    jr     nc,ZEROOUT            ; output a zero if no carry
ONEOUT:
    or     dioport,#doh          ; set the data out high
    or     clkport,#clockh       ; set the clock high
    and    clkport,#clockl       ; reset the clock low
    and    dioport,#dol          ; reset the data out low
    djnz   templ,SERIALOUTLOOP   ; loop till done
    ret                                ; return
ZEROOUT:
    and    dioport,#dol          ; reset the data out low
    or     clkport,#clockh       ; set the clock high
    and    clkport,#clockl       ; reset the clock low
    and    dioport,#dol          ; reset the data out low
    djnz   templ,SERIALOUTLOOP   ; loop till done
    ret                                ; return

```

SERIAL IN
INPUTS A BYTE TO SERIAL

SERIALIN:

```

    or     P2M_SHADOW, #doh      ; Force the data line to input
    ld     P2M,P2M_SHADOW        ; set port 2 mode forcing input mode data
    ld     templ,#8H             ; set the count for eight bits
SERIALINLOOP:
    or     clkport,#clockh       ; set the clock high
    rcf                                ; reset the carry flag
    ld     temph,dioport         ; read the port
    and    temph,#doh            ; mask out the bits
    jr     z,DONTSET
    scf                                ; set the carry flag
DONTSET:
    rlc    serial                ; get the bit into the byte
    and    clkport,#clockl       ; reset the clock low
    djnz   templ,SERIALINLOOP   ; loop till done
    ret                                ; return

```

; TIMER UPDATE FROM INTERRUPT EVERY 0.256ms

SkipPulse:

```

;   tm     SKIPRADIO, #NOINT      ;If the 'no radio interrupt'
;   jr     nz, NoPulse           ;flag is set, just leave
;   or     IMR,#RadioImr         ; turn on the radio
;NoPulse:
    iret

```

TIMERUD:

```

    tm     SKIPRADIO, #NOINT      ;If the 'no radio interrupt'
    jr     nz, NoEnable          ;flag is set, just leave
    or     IMR,#RadioImr         ; turn on the radio
NoEnable:
    decw   T0EXTWORD             ; decrement the T0 extension
TOExtDone:
    tm     P2, #LINEINPIN        ; Test the AC line in
    jr     z, LowAC              ; If it's low, mark zero crossing
HighAC:

```

```

inc    LineCtr                ; Count the high time
jr     LineDone                ;
LowAC:
cp     LineCtr, #08            ; If the line was low before
jr     ult, HighAC             ; then one-shot the edge of the line
ld     LinePer, LineCtr        ; Store the high time
clr    LineCtr                ; Reset the counter
ld     PhaseTMR, PhaseTime     ; Reset the timer for the phase control

LineDone:
cp     PowerLevel, #20         ; Test for at full wave of phase
jr     uge, PhaseOn           ; If not, turn off at the start of the phase
cp     PowerLevel, #00         ; If we're at the minimum,
jr     z, PhaseOff            ; then never turn the phase control on
dec    PhaseTMR               ; Update the timer for phase control
jr     ml, PhaseOn            ; If we are past the zero point, turn on the line

PhaseOff:
and    PhasePrt, #-PhaseHigh   ; Turn off the phase control
jr     PhaseDone              ;

PhaseOn:
or     PhasePrt, #PhaseHigh    ; Turn on the phase control

PhaseDone:
tm     P3, #00000010b          ; Test the RPM in pin
jr     nz, IncRPMDB           ; If we're high, increment the filter
DecRPMDB:
cp     RPM_FILTER, #00         ; Decrement the value of the filter if
jr     z, RPMFiltered         ; we're not already at zero
dec    RPM_FILTER             ;
jr     RPMFiltered            ;
IncRPMDB:
inc    RPM_FILTER             ; Increment the value of the filter
jr     nz, RPMFiltered        ; and back turn if necessary
dec    RPM_FILTER             ;

RPMFiltered:
cp     RPM_FILTER, #12         ; If we've seen 2.5 ms of high time
jr     z, VectorRPMHigh       ; then vector high
cp     RPM_FILTER, #(255 - 12) ; If we've seen 2.5 ms of low time
jr     nz, TaskSwitcher       ; then vector low

VectorRPMLow:
clr    RPM_FILTER             ;
jr     TaskSwitcher           ;

VectorRPMHigh:
ld     RPM_FILTER, #0FFH       ;

TaskSwitcher
tm     TOEXT, #00000001b       ; skip everyother pulse
jr     nz, SkipPulse
tm     TOEXT, #00000010b       ; Test for odd numbered task
jr     nz, TASK1357           ; If so do the lms timer update
tm     TOEXT, #00000100b       ; Test for task 2 or 6
jr     z, TASK04              ; If not, then go to Tasks 0 and 4
tm     TOEXT, #00001000b       ; Test for task 6
jr     nz, TASK6              ; If so, jump
                                           ; Otherwise, we must be in task 2

TASK2:
or     IMR, #RETURN_IMR       ; turn on the interrupt
ei
call   STATEMACHINE           ; do the motor function
iret

TASK04:

```

```

or      IMR,#RETURN_IMR          ; turn on the interrupt
ei
push    rp                      ; save the rp
srp     #TIMER_GROUP             ; set the rp for the switches
call    switches                 ; test the switches
pop     rp
iret

TASK6:
or      IMR,#RETURN_IMR          ; turn on the interrupt
ei
call    TIMER4MS                 ; do the four ms timer
iret

TASK1357:
push    RP
or      IMR,#RETURN_IMR          ; turn on the interrupt
ei

ONEMS:
tm      p0,#DOWN_COMP            ; Test down force pot.
jr      nz,HigherDn              ; Average too low -- output pulse
PowerDn:
and     p3,#(~DOWN_OUT)          ; take pulse output low
jr      DnPotDone
HigherDn:
or      p3,#DOWN_OUT             ; Output a high pulse
inc     DN_TEMP                  ; Increase measured duty cycle
DnPotDone:
tm      p0,#UP_COMP              ; Test the up force pot.
jr      nz,HigherUp              ; Average too low -- output pulse
LowerUp:
and     P3,#(~UP_OUT)            ; Take pulse output low
jr      UpPotDone
HigherUp:
or      P3,#UP_OUT               ; Output a high pulse
inc     UP_TEMP                  ; Increase measured duty cycle
UpPotDone:
inc     POT_COUNT                ; Increment the total period for
jr      nz,GoTimer              ; duty cycle measurement
rcf     UP_TEMP                  ; Divide the pot values by two to obtain
rrc     UP_TEMP                  ; a 64-level force range.
rcf     DN_TEMP                  ;
rrc     DN_TEMP                  ;
di      ; Subtract from 63 to reverse the direction
ld      UPFORCE, #63             ; Calculate pot. values every 255
sub     UPFORCE, UP_TEMP          ; counts
ld      DNFORCE, #63             ;
sub     DNFORCE, DN_TEMP          ;
ei      ;
clr     UP_TEMP                  ; counts
clr     DN_TEMP                  ;

GoTimer:
srp     #LEARNER_GRP             ; set the register pointer
dec     AOBSTEST                 ; decrease the aobs test timer
jr      nz,NOFAIL                ; if the timer not at 0 then it didnot fail
ld      AOBSTEST,#11             ; if it failed reset the timer
tm      AOBSF,#00100000b         ; If the aobs was blocked before,
jr      nz,BlockedBeam           ; don't turn on the light
or      AOBSF,#10000000b         ; Set the break edge flag

BlockedBeam:
or      AOBSF,#00100001b         ; Set the single break flag

NOFAIL:
inc     RadioTimeOut
cp      OBS_COUNT, #00           ; Test for protector timed out
jr      z,TEST125                ; If it has failed, then don't decrement

```

```

dec     OBS_COUNT           ; Decrement the timer

PPointDeb:
di                      ; Disable ints while debouncer being modified (16us)
tm     PPointPort, #PassPoint ; Test for pass point being seen
jr     nz, IncPPDeb       ; If high, increment the debouncer

DecPPDeb:
and     PPOINT_DEB, #00000011b ; Debounce 3-0
jr     z, PPDebDone       ; If already zero, don't decrement
dec     PPOINT_DEB        ; Decrement the debouncer
jr     PPDebDone          ;

IncPPDeb:
inc     PPOINT_DEB        ; Increment 0-3 debouncer
and     PPOINT_DEB, #00000011B ;
jr     nz, PPDebDone      ; If rolled over,
ld     PPOINT_DEB, #00000011B ; keep it at the max.

PPDebDone:
ei                      ; Re-enable interrupts

TEST125:
inc     t125ms           ; increment the 125 mS timer
cp     t125ms, #125      ; test for the time out
jr     z, ONE25MS        ; if true the jump
cp     t125ms, #63       ; test for the other timeout
jr     nz, N125
call   FAULTB

N125:
pop     RP
iret

ONE25MS:
cp     RsMode, #00       ; Test for not in RS232 mode
jr     z, CheckSpeed     ; If not, don't update RS timer
dec     RsMode           ; Count down RS232 time
jr     nz, CheckSpeed    ; If not done yet, don't clear wall
ld     STATUS, #CHARGE   ; Revert to charging wall control

CheckSpeed:
cp     RampFlag, #STILL   ; Test for still motor
jr     z, StopMotor      ; If so, turn off the FET's
tm     BLINK_HI, #10000000b ; If we are flashing the warning light,
jr     z, StopMotor      ; then don't ramp up the motor
cp     L_A_C, #076H       ; Special case -- use the ramp-down
jr     z, NormalRampFlag ; when we're going to the learned up limit
cp     L_A_C, #070H       ; If we're learning limits,
jr     uge, RunReduced   ; then run at a slow speed

NormalRampFlag:
cp     RampFlag, #RAMPDOWN ; Test for slowing down
jr     z, SlowDown       ; If so, slow to minimum speed

SpeedUp:
cp     PowerLevel, MaxSpeed ; Test for at max. speed
jr     uge, SetAtFull    ; If so, leave the duty cycle alone

RampSpeedUp:
inc     PowerLevel        ; Increase the duty cycle of the phase
jr     SpeedDone          ;

SlowDown:
cp     PowerLevel, MinSpeed ; Test for at min. speed
jr     ult, RampSpeedUp   ; If we're below the minimum, ramp up to it
jr     z, SpeedDone       ; If we're at the minimum, stay there
dec     PowerLevel        ; Increase the duty cycle of the phase
jr     SpeedDone          ;

RunReduced:
ld     RampFlag, #FULLSPEED ; Flag that we're not ramping up
cp     MinSpeed, #8       ; Test for high minimum speed
jr     ugt, PowerAtMin    ;
ld     PowerLevel, #8     ; Set the speed at 40%
jr     SpeedDone          ;

PowerAtMin:
ld     PowerLevel, MinSpeed ; Set power at higher minimum
jr     SpeedDone          ;

StopMotor:

```



```

protection)    clr    PowerLevel          ; Make sure that the motor is stopped (FMEA
SetAtFull:     jr     SpeedDone            ;
SpeedDone:     ld     RampFlag, #FULLSPEED ; Set flag for done with ramp-up
SixtySpeed:    cp     LinePer, #36          ; Test for 50Hz or 60Hz
               jr     uge, FiftySpeed      ; Load the proper table
               di                      ; Disable interrupts to avoid pointer collision
               srp     #RadioGroup         ; Use the radio pointers to do a ROM fetch
               ld     pointerh, #HIGH(SPEED_TABLE_60) ; Point to the force look-up table
               ld     pointerl, #LOW(SPEED_TABLE_60) ;
               add     pointerl, PowerLevel ; Offset for current phase step
               adc     pointerh, #00H       ;
               ldc     addvalueh, @pointer  ; Fetch the ROM data for phase control
               ld     PhaseTime, addvalueh ; Transfer to the proper register
               ei                      ; Re-enable interrupts
               jr     WorkCheck            ; Check the worklight toggle

FiftySpeed:    di                      ; Disable interrupts to avoid pointer collision
               srp     #RadioGroup         ; Use the radio pointers to do a ROM fetch
               ld     pointerh, #HIGH(SPEED_TABLE_50) ; Point to the force look-up table
               ld     pointerl, #LOW(SPEED_TABLE_50) ;
               add     pointerl, PowerLevel ; Offset for current phase step
               adc     pointerh, #00H       ;
               ldc     addvalueh, @pointer  ; Fetch the ROM data for phase control
               ld     PhaseTime, addvalueh ; Transfer to the proper register
               ei                      ; Re-enable interrupts

WorkCheck:     srp     #LEARNEE_GRP        ; Re-set the RP
               ; 4-22-97
               CP      EnableWorkLight, #01100000B
               JR      EQ, DontInc          ; Has the button already been held for 10s?
               INC     EnableWorkLight      ; Work light function is added to every
               ; 125ms if button is light button is held
               ; for 10s will initiate change, if not held
               ; down will be cleared in switch routine

DontInc:       cp     AUXLEARNsw, #OFFh     ; test for the rollover position
               jr     z, SKIPAUXLEARNsw     ; if so then skip
               inc     AUXLEARNsw           ; increase

SKIPAUXLEARNsw:
               cp     ZZWIN, #OFFh          ; test for the roll position
               jr     z, TESTFA             ; if so skip
               inc     ZZWIN                ; if not increase the counter

TESTFA:        call   FAULTB               ; call the fault blinker
               clr     T125MS               ; reset the timer
               inc     DOG2                  ; increase the second watch dog
               di                      ;
               inc     SDISABLE              ; count off the system disable timer
               jr     nz, DO12               ; if not rolled over then do the 1.2 sec
               dec     SDISABLE              ; else reset to FF

DO12:          cp     ONEP2, #00            ; test for 0
               jr     z, INCLEARN           ; if counted down then increment learn
               dec     ONEP2                ; else down count

INCLEARN:      inc     learnt               ; increase the learn timer
               cp     learnt, #0H           ; test for overflow
               jr     nz, LEARNTOX         ; if not 0 skip back turning
               dec     learnt               ;

LEARNTOX:      ei                      ;
               inc     eraset               ; increase the erase timer
               cp     eraset, #0H          ; test for overflow
               jr     nz, ERASETOX         ; if not 0 skip back turning

```

```

    dec    eraset
ERASETOK:
    pop    RP
    iret

;    fault blinker

FAULTB:
    inc    FAULTTIME                ; increase the fault timer
    cp     L_A_C, #070H             ; Test for in learn limits mode
    jr     ult, DoFaults           ; If not, handle faults normally
    cp     L_A_C, #071H             ; Test for failed learn
    jr     z, FastFlash            ; If so, blink the LED fast

RegFlash:
    tm     FAULTTIME, #00000100b    ; Toggle the LED every 250ms
    jr     z, FlashOn

FlashOff:
    or     ledport, #ledh           ; Turn off the LED for blink
    jr     NOFAULT                 ; Don't test for faults

FlashOn:
    and    ledport, #ledl           ; Turn on the LED for blink
    jr     NOFAULT

FastFlash:
    tm     FAULTTIME, #00000010b    ; Toggle the LED every 125ms
    jr     z, FlashOn
    jr     FlashOff

DoFaults:
    cp     FAULTTIME, #80h          ; test for the end
    jr     nz, FIRSTFAULT          ; if not timed out
    clr     FAULTTIME              ; reset the clock
    clr     FAULT                  ; clear the last
    cp     FAULTCODE, #05h         ; test for call dealer code
    jr     UGE, GOTFAULT           ; set the fault
    cp     CMD_DEB, #0FFH          ; test the debouncer
    jr     nz, TESTAOBSM           ; if not set test aobs
    cp     FAULTCODE, #03h         ; test for command shorted
    jr     z, GOTFAULT            ; set the error
    ld     FAULTCODE, #03h         ; set the code
    jr     FIRSTFAULT

TESTAOBSM:
    tm     AOBSF, #00000001b        ; test for the skipped aobs pulse
    jr     z, NOAOBSFAULT          ; if no skips then no faults
    tm     AOBSF, #00000010b        ; test for any pulses
    jr     z, NOPULSE             ; if no pulses find if hi or low
    ; else we are intermittent
    ld     FAULTCODE, #04h         ; set the fault
    jr     GOTFAULT               ; if same got fault
    cp     FAULTCODE, #04h         ; test the last fault
    jr     z, GOTFAULT            ; if same got fault
    ld     FAULTCODE, #04h         ; set the fault
    jr     FIRSTFC

NOPULSE:
    tm     P3, #00000001b          ; test the input pin
    jr     z, AOBSSH              ; jump if aobs is stuck hi
    cp     FAULTCODE, #01h         ; test for stuck low in the past
    jr     z, GOTFAULT            ; set the fault
    ld     FAULTCODE, #01h         ; set the fault code
    jr     FIRSTFC

AOBSSH:
    cp     FAULTCODE, #02h         ; test for stuck high in past
    jr     z, GOTFAULT            ; set the fault
    ld     FAULTCODE, #02h         ; set the code
    jr     FIRSTFC

GOTFAULT:
    ld     FAULT, FAULTCODE        ; set the code
    swap   FAULT
    jr     FIRSTFC

NOAOBSFAULT:
    clr     FAULTCODE              ; clear the fault code

FIRSTFC:
    and    AOBSF, #11111100b      ; clear flags

```

FIRSTFAULT:

```

tm    FAULTTIME, #00000111b    ; If one second has passed,
jr    nz, RegularFault        ; increment the 60min

incw   HOUR_TIMER              ; Increment the 1 hour timer
tcm    HOUR_TIMER_LO, #00011111b ; If 32 seconds have passed
jr    nz, RegularFault        ; poll the radio mode

or     AOBFSF, #01000000b      ; Set the 'poll radio' flag

```

RegularFault:

```

cp     FAULT, #00              ; test for no fault
jr     z, NOFAULT
ld     FAULTFLAG, #OFFH        ; set the fault flag
cp     CodeFlag, #REGLEARN     ; test for not in learn mode
jr     z, TESTSDI              ; if in learn then skip setting
cp     FAULT, FAULTTIME        ;
jr     ULE, TESTSDI

tm     FAULTTIME, #00001000b    ; test the 1 sec bit
jr     nz, BITONE
and    ledport, #ledl          ; turn on the led
ret

```

BITONE:

```

or     ledport, #ledh          ; turn off the led

```

TESTSDI:

```

ret

```

NOFAULT:

```

clr    FAULTFLAG              ; clear the flag
ret

```

Four ms timer tick routines and aux light function

TIMER4MS:

```

cp     RPMONES, #00H          ; test for the end of the one sec timer
jr     z, TESTPERIOD          ; if one sec over then test the pulses
                                   ; over the period
dec     RPMONES                ; else decrease the timer
di
clr     RPM_COUNT              ; start with a count of 0
clr     BRPM_COUNT             ; start with a count of 0
ei
jr     RPMTDONE

```

TESTPERIOD:

```

cp     RPMCLEAR, #00H         ; test the clear test timer for 0
jr     nz, RPMTDONE           ; if not timed out then skip
ld     RPMCLEAR, #122         ; set the clear test time for next cycle .5
cp     RPM_COUNT, #50         ; test the count for too many pulses
jr     ugt, FAREV             ; if too man pulses then reverse
di
clr     RPM_COUNT              ; clear the counter
clr     BRPM_COUNT            ; clear the counter
ei
;
clr     FAREVFLAG              ; clear the flag    temp test
jr     RPMTDONE               ; continue

```

FAREV:

```

ld     FAULTCODE, #06h        ; set the fault flag
ld     FAREVFLAG, #088H       ; set the forced up flag
and    p0, #LOW(~WORKLIGHT)   ; turn off light
ld     REASON, #80H           ; rpm forcing up motion
call   SET_AREV_STATE         ; set the autorev state

```

RPMTDONE:

```

dec     RPMCLEAR              ; decrement the timer

```

```

        cp    LIGHT1S,#00`          ; test for the end
        jr    z,SKIPLIGHTE
        dec    LIGHT1S              ; down count the light time

SKIPLIGHTE:
        inc    R_DEAD_TIME
        cp    RTO,#RDROPTIME        ; test for the radio time out
        jr    ult,DONOTCB           ; if not timed out donot clear b
        cp    CodeFlag,#LRNOCS      ; If we are in a special learn mode,
        jr    uge,DONOTCB           ; then don't clear the code flag
        clr    CodeFlag             ; else clear the b code flag

DONOTCB:
        inc    RTO                  ; increment the radio time out
        jr    nz,RTOOK              ; if the radio timeout ok then skip
        dec    RTO                  ; back turn

RTOOK:
        cp    RRTO,#OFFH            ; test for roll
        jr    z,SKIPRRTO            ; if so then skip
        inc    RRTO

SKIPRRTO:
        cp    SKIPRADIO,#00         ; Test for EEPROM communication
        jr    nz,LEARNDDBOK         ; If so, skip reading program switch
        cp    RsMode,#00            ; Test for in RS232 mode,
        jr    nz,LEARNDDBOK         ; if so, don't update the debouncer
        tm    psport,#psmask        ; Test for program switch
        jr    z,PRSWCLOSED          ; if the switch is closed count up
        cp    LEARNDB,#00           ; test for the non decrement point
        jr    z,LEARNDDBOK         ; if at end skip dec
        dec    LEARNDB
        jr    LEARNDBOK

PRSWCLOSED:
        cp    LEARNDB,#OFFH         ; test for debouncer at max.
        jr    z,LEARNDDBOK         ; if not at max increment
        inc    LEARNDE              ; increase the learn debounce timer

LEARNDDBOK:

```

----- AUX OBSTRUCTION OUTPUT AND LIGHT FUNCTION -----

```

AUXLIGHT:
test_light_on:
        cp    LIGHT_FLAG,#LIGHT    ;
        jr    z,dec_light           ;
        cp    LIGHT1S,#00           ; test for no flash
        jr    z,N01S               ; if not skip
        cp    LIGHT1S,#1            ; test for timeout
        jr    nz,N01S              ; if not skip
        xor    p0,#WORKLIGHT        ; toggle light
        clr    LIGHT1S              ; oneshoted

N01S:
        cp    FLASH_FLAG,#FLASH
        jr    nz,dec_light          ;
        clr    VACFLASH              ; Keep the vacation flash timer off
        dec    FLASH_DELAY           ; 250 ms period
        jr    nz,dec_light          ;

        cp    STATUS,#RSSTATUS      ; Test for in RS232 mode
        jr    z,BlinkDone           ; If so, don't blink the LED
        ; Toggle the wall control LED
        cp    STATUS,#WALLOFF       ; See if the LED is off or on
        jr    z,TurnItOn            ;

TurnItOff:
        ld    STATUS,#WALLOFF        ; Turn the light off
        jr    BlinkDone              ;

TurnItOn:
        ld    STATUS,#CHARGE          ; Turn the light on
        ld    SWITCH_DELAY,#CMD_DEL_EX ; Reset the delay time for charge

BlinkDone:
        ld    FLASH_DELAY,#FLASH_TIME

```

```

    dec    FLASH_COUNTER          ;
    jr     nz,dec_light
    clr    FLASH_FLAG            ;
dec_light:
    cp     LIGHT_TIMER_HI,#OFFH   ; test for the timer ignore
    jr     z,exit_light           ; if set then ignore
    tm     T0EXT, #00010000b      ; Decrement the light every 8 ms
    jr     nz,exit_light          ; (Use T0Ext to prescale)
    decw   LIGHT_TIMER            ;
    jr     nz,exit_light          ; if timer 0 turn off the light
    and    p0,#(~LIGHT_ON)        ; turn off the light
    cp     L_A_C, #00             ; Test for in a learn mode
    jr     z, exit_light          ; If not, leave the LED alone
    clr    L_A_C                  ; Leave the learn mode
    or     ledport,#ledh          ; turn off the LED for program mode
exit_light:
    ret                           ; return

```

; MOTOR STATE MACHINE

```

STATEMACHINE:
    cp     MOTDEL, #OFFH          ; Test for max. motor delay
    jr     z, MOTDELDONE          ; if do, don't increment
    inc    MOTDEL                 ; update the motor delay
MOTDELDONE:
    xor    p2,#FALSEIR           ; toggle aux output
    cp     DOG2,#8                ; test the 2nd watchdog for problem
    jp     ugt,START              ; if problem reset
    cp     STATE,#6               ; test for legal number
    jp     ugt,start              ; if not the reset
    jp     z,stop                 ; stop motor 6
    cp     STATE,#3               ; test for legal number
    jp     z,start                ; if not the reset
    cp     STATE,#0               ; test for autorev
    jp     z,auto_rev             ; auto reversing 0
    cp     STATE,#1               ; test for up
    jp     z,up_direction         ; door is going up 1
    cp     STATE,#2               ; test for autorev
    jp     z,up_position          ; door is up 2
    cp     STATE,#4               ; test for autorev
    jp     z,dn_direction         ; door is going down 4
    jp     dn_position            ; door is down 5

```

; AUTO_REV ROUTINE

```

auto_rev:
    cp     FAREVFLAG,#08SH        ; test for the forced up flag
    jr     nz,LEAVEREV
    and    p0,#LOW(~WORKLIGHT)    ; turn off light
    ;     clr    FAREVFLAG        ; one shot temp test
LEAVEREV:
    cp     MOTDEL, #10            ; Test for 40 ms passed
    jr     ult, AREVON            ; If not, keep the relay on
AREVOFF:
    and    p0,#LOW(~MOTOR_UP & ~MOTOR_DN) ; disable motor
AREVON:
    WDT                                ; kick the dog
    call   HOLDFREY               ; hold off the force reverse
    ld     LIGHT_FLAG,#LIGHT      ; force the light on no blink
    di
    dec    AUTO_DELAY             ; wait for .5 second
    dec    BAUTO_DELAY            ; wait for .5 second
    ei

```

```

jr      nz, arswitch          ; test switches

or      p2, #FALSEIR         ; set aux output    for FEMA

; LOOK FOR LIMIT HERE (No)
ld      REASON, #40H          ; set the reason for the change
cp      L_A_C, #075H          ; Check for learning limits,
jp      nz, SET_UP_NOBLINK    ; If not, proceed normally
ld      L_A_C, #076H          ;
jp      SET_UP_NOBLINK        ; set the state

arswitch:
ld      REASON, #00H          ; set the reason to command
di
cp      SW_DATA, #CMD_SW      ; test for a command
clr     SW_DATA
ei
jp      z, SET_STOP_STATE     ; if so then stop
ld      REASON, #10H          ; set the reason as radio command
cp      RADIO_CMD, #0AAH      ; test for a radio command
jp      z, SET_STOP_STATE     ; if so the stop

exit_auto_rev:
ret                                ; return

HOLDFREY:
ld      RPMONES, #244          ; set the hold off
ld      RPMCLEAR, #122        ; clear rpm reverse .5 sec
di
clr     RPM_COUNT              ; start with a count of 0
clr     BRPM_COUNT             ; start with a count of 0
ei
ret

-----
DOOR GOING UP
-----

up_direction:
WDT                                ; kick the dog
cp      OnePass, STATE         ; Test for the memory read one-shot
jr      z, UpReady             ; If so, continue
ret                                ; Else wait

UpReady:
call    HOLDFREY               ; hold off the force reverse
ld      LIGHT_FLAG, #LIGHT     ; force the light on no blink
and     p0, #LOW(~MOTOR_DN)    ; disable down relay

or      p0, #LIGHT_ON          ; turn on the light
cp      MOTDEL, #10            ; test for 40 milliseconds
jr      ule, UPOFF             ; if not timed

CheckUpBlink:
and     P2M_SHADOW, #~BLINK_PIN ; Turn on the blink output
ld      P2M, P2M_SHADOW        ;
or      P2, #BLINK_PIN         ; Turn on the blinker
decw    BLINK                  ; Decrement blink time
tm      BLINK_HI, #10000000b    ; Test for pre-travel blinking done
jp      z, NotUpSlow           ; If not, delay normal motor travel

UPON:
or      p0, #(MOTOR_UP | LIGHT_ON) ; turn on th motor and light

UPOFF:
cp      FORCE_IGNORE, #1        ; test fro the end of the force ignore
jr      nz, SKIPUPRPM          ; if not donot test rpmcount
cp      RPM_ACOUNT, #12H      ; test for less the 2 pulses
jr      ugt, SKIPUPRPM         ;
ld      FAULTCODE, #05H

SKIPUPRPM:

```

```

    cp    FORCE_IGNORE, #00                ; test timer for done
    jr    nz, test_up_sw_pre              ; if timer not up do not test force
TEST_UP_FORCE:
    di
    dec    RPM_TIME_OUT                  ; decrease the timeout
    dec    BRPM_TIME_OUT                 ; decrease the timeout
    ei
    jr    z, failed_up_rpm
    cp    RampFlag, #RAMPUP              ; Check for ramping up the force
    jr    z, test_up_sw                  ; If not, always do full force check
TestUpForcePot:
    di                                    ; turn off the interrupt
    cp    RPM_PERIOD_HI, UP_FORCE_HI ; Test the RPM against the force setting
    jr    ugt, failed_up_rpm
    jr    ult, test_up_sw
    cp    RPM_PERIOD_LO, UP_FORCE_LO ;
    jr    ult, test_up_sw
failed_up_rpm:
    ld    REASON, #20H                    ; set the reason as force
    cp    L_A_C, #076H                    ; If we're learning limits,
    jp    nz, SET_STOP_STATE              ; then set the flag to store
    ld    L_A_C, #077H
    jp    SET_STOP_STATE
test_up_sw_pre:
    di
    dec    FORCE_IGNORE
    dec    BFORCE_IGNORE
test_up_sw:
    di
    ld    LIM_TEST_HI, POSITION_HI        ; Calculate the distance from the up limit
    ld    LIM_TEST_LO, POSITION_LO
    sub    LIM_TEST_LO, UP_LIMIT_LO
    sbc    LIM_TEST_HI, UP_LIMIT_HI
    cp    POSITION_HI, #0B0H                ; Test for lost door
    jr    ugt, UpPosKnown                ; If not lost, limit test is done
    cp    POSITION_HI, #050H
    jr    ult, UpPosKnown
    ei
UpPosUnknown:
    sub    LIM_TEST_LO, #062H            ; Calculate the total travel distance allowed
    sbc    LIM_TEST_HI, #07FH            ; from the floor when lost
    add    LIM_TEST_LO, DN_LIMIT_LO
    adc    LIM_TEST_HI, DN_LIMIT_HI
UpPosKnown:
    ei
    cp    L_A_C, #070H                    ; If we're positioning the door, forget the limit
    jr    z, test_up_time                ; and the wall control and radio
    cp    LIM_TEST_HI, #00                ; Test for exactly at the limit
    jr    nz, TestForPastUp              ; If not, see if we've passed the limit
    cp    LIM_TEST_LO, #00
    jr    z, AtUpLimit
TestForPastUp:
    tm    LIM_TEST_HI, #10000000b        ; Test for a negative result (past the limit, but
close)
    jr    z, get_sw                        ; If so, set the limit
AtUpLimit:
    ld    REASON, #50H                    ; set the reason as limit
    cp    L_A_C, #072H                    ; If we're re-learning limits,
    jr    z, ReLearnLim                  ; jump
    cp    L_A_C, #076H                    ; If we're learning limits,
    jp    nz, SET_UP_POS_STATE            ; then set the flag to store
    ld    L_A_C, #077H
    jp    SET_UP_POS_STATE
ReLearnLim:
    ld    L_A_C, #073H
    jp    SET_UP_POS_STATE
get_sw:
    cp    L_A_C, #070H                    ; Test for positioning the up limit
    jr    z, NotUpSlow                    ; If so, don't slow down

```

```

TestUpSlow:
    cp    LIM_TEST_HI, #HIGH(UPSLOWSTART) ; Test for start of slowdown
    jr    nz, NotUpSlow ; (Cheating -- the high byte of the number is zero)
    cp    LIM_TEST_LO, #LOW(UPSLOWSTART) ;
    jr    ugt, NotUpSlow ;

UpSlow:
    ld    RampFlag, #RAMPDOWN ; Set the slowdown flag

NotUpSlow:
    ld    REASON, #10H ; set the radio command reason
    cp    RADIO_CMD, #0AAH ; test for a radio command
    jp    z, SET_STOP_STATE ; if so stop
    ld    REASON, #00H ; set the reason as a command
    di
    cp    SW_DATA, #CMD_SW ; test for a command condition
    clr    SW_DATA
    ei
    jr    ne, test_up_time ;
    jp    SET_STOP_STATE ;

test_up_time:
    ld    REASON, #70H ; set the reason as a time out
    decw    MOTOR_TIMER ; decrement motor timer
    jp    z, SET_STOP_STATE ;

exit_up_dir:
    ret ; return to caller
-----
DOOR UP
-----
Up_position:
    WDT ; kick the dog
    cp    FAREVFLAG, #088H ; test for the forced up flag
    jr    nz, LEAVELIGHT
    and    p0, #LOW(~WORKLIGHT) ; turn off light
    jr    UPNOFLASH ; skip clearing the flash flag
LEAVELIGHT:
    ld    LIGHT_FLAG, #00H ; allow blink
UPNOFLASH:
    cp    MOTDEL, #10 ; Test for 40 ms passed
    jr    ult, UPLIMON ; If not, keep the relay on
UPLIMOFF:
    and    p0, #LOW(~MOTOR_UP & ~MOTOR_DN) ; disable motor
UPLIMON:
    cp    L_A_C, #073H ; If we've begun the learn limits cycle,
    jr    z, LACUPPOS ; then delay before traveling
    cp    SW_DATA, #LIGHT_SW ; light sw debounced?
    jr    z, work_up ;
    ld    REASON, #10H ; set the reason as a radio command
    cp    RADIO_CMD, #0AAH ; test for a radio cmd
    jr    z, SETDNDIRSTATE ; if so start down
    ld    REASON, #00H ; set the reason as a command
    di
    cp    SW_DATA, #CMD_SW ; command sw debounced?
    clr    SW_DATA
    ei
    jr    z, SETDNDIRSTATE ; if command
    ret
SETDNDIRSTATE:
    ld    ONEP2, #10 ; set the 1.2 sec timer
    jp    SET_DN_DIR_STATE

LACUPPOS:
    cp    MOTOR_TIMER_HI, #HIGH(LACTIME); Make sure we're set to the proper time
    jr    ule, UpTimeOk
    ld    MOTOR_TIMER_HI, #HIGH(LACTIME)
    ld    MOTOR_TIMER_LO, #LOW(LACTIME)

UpTimeOk:
    decw    MOTOR_TIMER ; Count down more time
    jr    nz, up_pos_ret ; If not timed out, leave

StartLACDown:

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ld    L_A_C, #074H          ; Set state as traveling down in LAC
clr   UP_LIMIT_HI           ; Clear the up limit
clr   UP_LIMIT_LO           ; and the position for
clr   POSITION_HI            ; determining the new up
clr   POSITION_LO            ; limit of travel
ld    PassCounter, #030H    ; Set pass points at max.
jp    SET_DN_DIR_STATE      ; Start door traveling down

work_up:
xor    p0, #WORKLIGHT       ; toggle work light
ld     LIGHT_TIMER_HI, #OFFH ; set the timer ignore
and    SW_DATA, #LOW(~LIGHT_SW) ; Clear the worklight bit

up_pos_ret:
ret                                ; return
;-----
; DOOR GOING DOWN
;-----

dn_direction:
WDT                                ; kick the dog
cp     OnePass, STATE          ; Test for the memory read one-shot
jr     z, DownReady           ; If so, continue
ret                                ; else wait

DownReady:
call   HOLDREV               ; hold off the force reverse
clr    FLASH_FLAG            ; turn off the flash
ld     LIGHT_FLAG, #LIGHT     ; force the light on no blink
and    p0, #LOW(~MOTOR_UP)    ; turn off motor up

or     p0, #LIGHT_ON          ; turn on the light
cp     MOTDEL, #10            ; test for 40 milliseconds
jr     ule, DNOFF             ; if not timed

CheckDnBlink:
and    P2M_SHADOW, #~BLINK_PIN ; Turn on the blink output
ld     P2M, P2M_SHADOW        ;
or     P2, #BLINK_PIN         ; Turn on the blinker
decw   BLINK                  ; Decrement blink time
tm     BLINK_HI, #10000000b    ; Test for pre-travel blink done
jr     z, NotDnSlow           ; If not, don't start the motor

DNON:

or     p0, #(MOTOR_DN | LIGHT_ON) ; turn on the motor and light

DNOFF:
cp     FORCE_IGNORE, #01       ; test fro the end of the force ignore
jr     nz, SKIPDNRPM          ; if not donot test rpmcount
cp     RPM_ACOUNT, #02H      ; test for less the 2 pulses
jr     ugt, SKIPDNRPM         ;
ld     FAULTCODE, #05h

SKIPDNRPM:
cp     FORCE_IGNORE, #00       ; test timer for done
jr     nz, test_dn_sw_pre     ; if timer not up do not test force

TEST_DOWN_FORCE:
di                                ; decrease the timeout
dec    RPM_TIME_OUT           ; decrease the timeout
dec    BRPM_TIME_OUT
ei
jr     z, failed_dn_rpm
cp     RampFlag, #RAMPUP      ; Check for ramping up the force
jr     z, test_dn_sw         ; If not, always do full force check

TestDownForcePot:
di                                ; turn off the interrupt
cp     RPM_PERIOD_HI, DN_FORCE_HI ; Test the RPM against the force setting
jr     ugt, failed_dn_rpm     ; if too slow then force reverse
jr     ult, test_dn_sw        ; if faster then we're fine
cp     RPM_PERIOD_LO, DN_FORCE_LO ;
jr     ult, test_dn_sw        ;

```

```

failed_dn_rpm:
    cp    L_A_C, #074H          ; Test for learning limits
    jp    z, DnLearnRev         ; If not, set the state normally
    tm    POSITION_HI, #11000000b ; Test for below last pass point
    jr    nz, DnRPMRev          ; if not, we're nowhere near the limit
    tm    LIM_TEST_HI, #10000000b ; Test for beyond the down limit
    jr    nz, DoDownLimit       ; If so, we've driven into the down limit

DnRPMRev:
    ld    REASON, #20H          ; set the reason as force
    cp    POSITION_HI, #0B0H      ; Test for lost,
    jp    ugt, SET_AREV_STATE    ; if not, autoreverse normally
    cp    POSITION_HI, #050H      ;
    jp    ult, SET_AREV_STATE    ;
    di                    ; Disable interrupts
    ld    POSITION_HI, #07FH      ; Reset lost position for max. travel up
    ld    POSITION_LO, #080H      ;
    ei                    ; Re-enable interrupts
    jp    SET_AREV_STATE        ;

DnLearnRev:
    ld    L_A_C, #075H          ; Set proper LAC
    jp    SET_AREV_STATE        ;

Test_dn_sw_pre:
    di
    dec    FORCE_IGNORE
    dec    BFORCE_IGNORE

Test_dn_sw:
    di
    cp    POSITION_HI, #050H      ; Test for lost in mid travel
    jr    ult, TestDnLimGood    ;
    cp    POSITION_HI, #0B0H      ; If so, don't test for limit until
    jr    ult, NotDnSlow        ; a proper pass point is seen

TestDnLimGood:
    ld    LIM_TEST_HI, DN_LIMIT_HI ; Measure the distance to the down limit
    ld    LIM_TEST_LO, DN_LIMIT_LO ;
    sub    LIM_TEST_LO, POSITION_LO ;
    sbc    LIM_TEST_HI, POSITION_HI ;
    ei

    cp    L_A_C, #070H          ; If we're in the learn cycle, forget the limit
    jr    uge, test_dn_time      ; and ignore the radio and wall control
    tm    LIM_TEST_HI, #10000000b ; Test for a negative result (past the down limit)
    jr    z, call_sw_dn          ; If so, set the limit
    cp    LIM_TEST_LO, #(255 - 36) ; Test for 36 pulses (3") beyond the limit
    jr    ugt, NotDnSlow        ; if not, then keep driving into the floor

DoDownLimit:
    ld    REASON, #50H          ; set the reason as a limit
    cp    CMD_DEB, #0FFH        ; test for the switch still held
    jr    nz, TESTRADIO         ;
    ld    REASON, #90H          ; closed with the control held
    jr    TESTFORCEIG

TESTRADIO:
    cp    LAST_CMD, #00          ; test for the last command being radio
    jr    nz, TESTFORCEIG       ; if not test force
    cp    CodeFlag, #BRECEIVED   ; test for the b code flag
    jr    nz, TESTFORCEIG       ;
    ld    REASON, #0A0H          ; set the reason as b code to limit

TESTFORCEIG:
    cp    FORCE_IGNORE, #00H      ; test the force ignore for done
    jr    z, NOAREVDN           ; a rev if limit before force enabled
    ld    REASON, #60H          ; early limit
    jp    SET_AREV_STATE        ; set autoreverse

NOAREVDN:
    and    p0, #LOW(~MOTOR_DN) ;
    jp    SET_DN_POS_STATE      ; set the state

call_sw_dn:
    cp    LIM_TEST_HI, #HIGH(DNSLOWSTART) ; Test for start of slowdown

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```

        jr      nz, NotDnSlow          ; (Cheating -- th high byte is zero)
        cp      LIM_TEST_LO, #LOW(DNSLOWSTART) ;
        jr      ugt, NotDnSlow        ;

DnSlow:
        ld      RampFlag, #RAMPDOWN    ; Set the slowdown flag

NotDnSlow:
        ld      REASON, #10H           ; set the reason as radio command
        cp      RADIO_CMD, #0AAH       ; test for a radio command
        jp      z, SET_AREV_STATE      ; if so arev
        ld      REASON, #00H           ; set the reason as command
        di
        cp      SW_DATA, #CMD_SW       ; test for command
        clr     SW_DATA
        ei
        jp      z, SET_AREV_STATE      ;

test_dn_time:
        ld      REASON, #70H           ; set the reason as timeout
        decw    MOTOR_TIMER            ; decrement motor timer
        jp      z, SET_AREV_STATE      ;

test_obs_count:
        cp      OBS_COUNT, #00         ; Test the obs count
        jr      nz, exit_dn_dir        ; if not done, don't reverse
        cp      FORCE_IGNORE, #(ONE_SEC / 2) ; Test for 0.5 second passed
        jr      ugt, exit_dn_dir       ; if within first 0.5 sec, ignore it
        cp      LAST_CMD, #00          ; test for the last command from radio.
        jr      z, OBSTESTB            ; if last command was a radio test b
        cp      CMD_DEB, #0FFH         ; test for the command switch holding
        jr      nz, OBSAREV            ; if the command switch is not holding
        ; do the autorev
        jr      exit_dn_dir            ; otherwise skip

OBSAREV:
        ld      FLASH_FLAG, #0FFH      ; set flag
        ld      FLASH_COUNTER, #20     ; set for 10 flashes
        ld      FLASH_DELAY, #FLASH_TIME ; set for .5 Hz period
        ld      REASON, #30H           ; set the reason as autoreverse
        jp      SET_AREV_STATE         ;

OBSTESTB:
        cp      CodeFlag, #BRECEIVED   ; test for the b code flag
        jr      nz, OBSAREV            ; if not b code then arev

exit_dn_dir:
        ret                            ; return

;-----
; DOOR DOWN
;-----

dn_position:
        WDT                                ; kick the dog
        cp      FAREVFLAG, #088H        ; test for the forced up flag
        jr      nz, DNLEAVEL            ;
        and     p0, #LOW(~WORKLIGHT)    ; turn off light
        jr      DNNOFLASH               ; skip clearing the flash flag

DNLEAVEL:
        ld      LIGHT_FLAG, #00H        ; allow blink

DNNOFLASH:
        cp      MOTDEL, #10             ; Test for 40 ms passed
        jr      ult, DNLMON             ; If not, keep the relay on

DNLIMOFF:
        and     p0, #LOW(~MOTOR_UP & ~MOTOR_DN) ; disable motor

DNLMON:
        cp      SW_DATA, #LIGHT_SW      ; debounced? light
        jr      z, work_dn              ;
        ld      REASON, #10H           ; set the reason as a radio command
        cp      RADIO_CMD, #0AAH       ; test for a radio command
        jr      z, SETUPDIRSTATE       ; if so go up
        ld      REASON, #00H           ; set the reason as a command
        di
        cp      SW_DATA, #CMD_SW       ; command sw pressed?

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    clr    SW_DATA
    ei
    jr     z, SETUPDIRSTATE          ; if so go up
    ret

SETUPDIRSTATE:
    ld     ONEP2, #10                ; set the 1.2 sec timer
    jp     SET_UP_DIR_STATE

work_dn:
    xor    p0, #WORKLIGHT            ; toggle work light
    ld     LIGHT_TIMER_HI, #OFFH      ; set the timer ignore
    and    SW_DATA, # LOW(~LIGHT_SW) ; Clear the worklight bit

dn_pos_ret:
    ret                                ; return

;-----
;      STOP
;-----

stop:
    WDT                                ; kick the dog
    cp     FAREVFLAG, #066H           ; test for the forced up flag
    jr     nz, LEAVESTOP
    and    p0, #LOW(~WORKLIGHT)       ; turn off light
    jr     STOPNOFLASH
LEAVESTOP:
    ld     LIGHT_FLAG, #00H           ; allow blink
STOPNOFLASH:
    cp     MOTDEL, #10                ; Test for 40 ms passed
    jr     ult, STOPMIDON             ; If not, keep the relay on
STOPMIDOFF:
    and    p0, #LOW(~MOTOR_UP & ~MOTOR_DN) ; disable motor
STOPMIDON:
    cp     SW_DATA, #LIGHT_SW         ; debounced? light
    jr     z, work_stop
    ld     REASON, #10H               ; set the reason as radio command
    cp     RADIO_CMD, #0AAH           ; test for a radio command
    jp     z, SET_DN_DIR_STATE        ; if so go down
    ld     REASON, #00H               ; set the reason as a command
    di
    cp     SW_DATA, #CMD_SW           ; command sw pressed?
    clr    SW_DATA
    ei
    jp     z, SET_DN_DIR_STATE        ; if so go down
    ret
work_stop:
    xor    p0, #WORKLIGHT            ; toggle work light
    ld     LIGHT_TIMER_HI, #OFFH      ; set the timer ignore
    and    SW_DATA, #LOW(~LIGHT_SW)  ; Clear the worklight bit

stop_ret:
    ret                                ; return

;-----
;      SET THE AUTOREV STATE
;-----

SET_AREV_STATE:
    di
    cp     L_A_C, #070H               ; Test for learning limits,
    jr     uge, LearningRev           ; If not, do a normal autoreverse

    cp     POSITION_HI, #020H          ; Look for lost position
    jr     ult, DoTheArev             ; If not, proceed as normal
    cp     POSITION_HI, #0D0H          ; Look for lost position
    jr     ugt, DoTheArev             ; If not, proceed as normal

; Otherwise, we're lost -- ignore commands
    cp     REASON, #020H              ; Don't respond to command or radio
    jr     uge, DoTheArev
    clr    RADIO_CMD                  ; Throw out the radio command

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        ei                                ; Otherwise, just ignore it
        ret                                ;

DoTheArev:

        ld    STATE, #AUTO_REV            ; if we got here, then reverse motor
        ld    RampFlag, #STILL            ; Set the FET's to off
        clr    PowerLevel                  ;
        jr     SET_ANY                     ; Done

LearningRev:
        ld    STATE, #AUTO_REV            ; if we got here, then reverse motor
        ld    RampFlag, #STILL            ; Set the FET's to off
        clr    PowerLevel                  ;
        cp    L_A_C, #075H                ; Check for proper reversal
        jr     nz, ErrorLearnArev          ; If not, stop the learn cycle
        cp    PassCounter, #030H          ; If we haven't seen a pass point,
        jr     z, ErrorLearnArev          ; then flag an error

GoodLearnArev:
        cp    POSITION_HI, #00              ; Test for down limit at least
        jr     nz, DnLimGood              ; 20 pulses away from pass point
        cp    POSITION_LO, #20              ;
        jr     ult, MovePassPoint         ; If not, use the upper pass point

DnLimGood:
        and    PassCounter, #10000000b    ; Set at lowest pass point

GotDnLim:
        di
        ld    DN_LIMIT_HI, POSITION_HI     ; Set the new down limit
        ld    DN_LIMIT_LO, POSITION_LO     ;
        add    DN_LIMIT_LO, #01            ; Add in a pulse to guarantee reversal off the block
        adc    DN_LIMIT_HI, #00            ;
        jr     SET_ANY                     ;

ErrorLearnArev:
        ld    L_A_C, #071H                ; Set the error in learning state
        jr     SET_ANY                     ;

MovePassPoint:
        cp    PassCounter, #02FH          ; If we have only one pass point,
        jr     z, ErrorLearnArev          ; don't allow it to be this close to the floor
        di
        add    POSITION_LO, #LOW(PPOINTPULSES) ; Use the next pass point up
        adc    POSITION_HI, #HIGH(PPOINTPULSES) ;
        add    UP_LIMIT_LO, #LOW(PPOINTPULSES) ;
        adc    UP_LIMIT_HI, #HIGH(PPOINTPULSES) ;
        ei
        or     PassCounter, #01111111b    ; Set pass counter at -1
        jr     GotDnLim                    ;

;-----
;   SET THE STOPPED STATE
;-----
SET_STOP_STATE:
        di
        cp    L_A_C, #070H                ; If we're in the learn mode,
        jr     uge, DoTheStop              ; Then don't ignore anything
        cp    POSITION_HI, #020H          ; Look for lost position
        jr     ult, DoTheStop              ; If not, proceed as normal
        cp    POSITION_HI, #0D0H          ; Look for lost position
        jr     ugt, DoTheStop              ; If not, proceed as normal

; Otherwise, we're lost -- ignore commands
        cp    REASON, #020H                ; Don't respond to command or radio
        jr     uge, DoTheStop              ;
        clr    RADIO_CMD                  ; Throw out the radio command
        ei                                ; Otherwise, just ignore it
        ret                                ;

DoTheStop:

```

```

ld    STATE, #STOP
ld    RampFlag, #STILL
clr   PowerLevel
jr    SET_ANY

;-----
;   SET THE DOWN DIRECTION STATE
;-----
SET_DN_DIR_STATE:

ld    BLINK_HI, #OFFH
call  LookForFlasher
tm    P2, #BLINK_PIN
jr    nz, SET_DN_NOBLINK
ld    BLINK_LO, #OFFH
ld    BLINK_HI, #01H

;Initially disable pre-travel blink
;Test to see if flasher present
;If the flasher is not present,
;don't flash it
;Turn on the blink timer
;

SET_DN_NOBLINK:

di
ld    RampFlag, #RAMPUP
ld    PowerLevel, #4
ld    STATE, #DN_DIRECTION
clr   FAREVFLAG

; Set the flag to accelerate motor
; Set speed at minimum
; energize door
; one shot the forced reverse

cp    L_A_C, #070H
jr    uge, SET_ANY

; If we're learning the limits,
; Then don't bother with testing anything

cp    POSITION_HI, #020H
jp    ult, SET_ANY
cp    POSITION_HI, #0D0H
jp    ugt, SET_ANY

; Look for lost position
; If not, proceed as normal
; Look for lost position
; If not, proceed as normal

lostDn:

cp    FirstRun, #00
jr    nz, SET_ANY
tm    PassCounter, #01111111b
jr    z, SET_UP_DIR_STATE
tcm   PassCounter, #01111111b
jr    z, SET_UP_DIR_STATE
jr    SET_ANY

; If this isn't our first operation when lost,
; then ALWAYS head down
; If we are below the lowest
; pass point, head up to see it
; If our pass point number is set at -1,
; then go up to find the position
; Otherwise, proceed normally

;-----
;   SET THE DOWN POSITION STATE
;-----
SET_DN_POS_STATE:

di
ld    STATE, #DN_POSITION
ld    RampFlag, #STILL
clr   PowerLevel
jr    SET_ANY

; load new state
; Stop the motor at the FET's
;

;-----
;   SET THE UP DIRECTION STATE
;-----
SET_UP_DIR_STATE:

ld    BLINK_HI, #OFFH
call  LookForFlasher
tm    P2, #BLINK_PIN
jr    nz, SET_UP_NOBLINK
ld    BLINK_LO, #OFFH
ld    BLINK_HI, #01H

;Initially turn off blink
;Test to see if flasher present
;If the flasher is not present,
;don't flash it
;Turn on the blink timer
;

SET_UP_NOBLINK:

di
ld    RampFlag, #RAMPUP
ld    PowerLevel, #4

; Set the flag to accelerate to max.
; Start speed at minimum

```

```

ld    STATE, #UP_DIRECTION      ;
jr    SET_ANY                    ;

;-----
;   SET THE UP POSITION STATE
;-----
SET_UP_POS_STATE:
di
ld    STATE, #UP_POSITION      ;
ld    RampFlag, #STILL          ; Stop the motor at the FET's
clr    PowerLevel                ;

;-----
;   SET ANY STATE
;-----
SET_ANY:
and    P2M_SHADOW, #-BLINK_PIN ; Turn on the blink output
ld     P2M, P2M_SHADOW          ;
and    P2, #-BLINK_PIN         ; Turn off the light

cp     PPOINT_DEB, #2           ; Test for pass point being seen
jr     ult, NoPrePPoint         ; If signal is low, none seen
PrePPoint:
or     PassCounter, #10000000b ; Flag pass point signal high
jr     PrePPointDone
NoPrePPoint:
and    PassCounter, #01111111b ; Flag pass point signal low
PrePPointDone:

ld     FirstRun, #OFFH          ; One-shot the first run flag DONE IN MAIN
ld     BSTATE, STATE           ; set the backup state
di
clr    RPM_COUNT               ; clear the rpm counter
clr    BRPM_COUNT              ;
ld     AUTO_DELAY, #AUTO_REV_TIME ; set the .5 second auto rev timer
ld     BAUTO_DELAY, #AUTO_REV_TIME ;
ld     FORCE_IGNORE, #ONE_SEC    ; set the force ignore timer to one sec
ld     BFORCE_IGNORE, #ONE_SEC  ; set the force ignore timer to one sec
ld     RPM_PERIOD_HI, #OFFH     ; Set the RPM period to max. to start
ei                                         ; Flush out any pending interrupts
di
cp     L_A_C, #070H             ; If we are in learn mode,
jr     uge, LearnModeMotor      ; don't test the travel distance
push   LIM_TEST_HI              ; Save the limit tests
push   LIM_TEST_LO              ;
ld     LIM_TEST_HI, DN_LIMIT_HI ; Test the door travel distance to
ld     LIM_TEST_LO, DN_LIMIT_LO ; see if we are shorter than 2.3M
sub    LIM_TEST_LO, UP_LIMIT_LO ;
sbc    LIM_TEST_HI, UP_LIMIT_HI ;
cp     LIM_TEST_HI, #HIGH(SHORTDOOR) ; If we are shorter than 2.3M,
jr     ugt, DoorIsNorm          ; then set the max. travel speed to 2/3
jr     ult, DoorIsShort         ; Else, normal speed
cp     LIM_TEST_LO, #LOW(SHORTDOOR) ;
jr     ugt, DoorIsNorm          ;

DoorIsShort:
ld     MaxSpeed, #12            ; Set the max. speed to 2/3
jr     DoorSet                  ;

DoorIsNorm:
ld     MaxSpeed, #20            ;

DoorSet:
pop     LIM_TEST_LO             ; Restore the limit tests
pop     LIM_TEST_HI             ;
ld     MOTOR_TIMER_HI, #HIGH(MOTORTIME)
ld     MOTOR_TIMER_LO, #LOW(MOTORTIME)

MotorTimeSet:
ei
clr    RADIO_CMD                ; one shot
clr    RPM_ACOUNT              ; clear the rpm active counter
ld     STACKREASON, REASON      ; save the temp reason

```

```

    ld    STACKFLAG,#OFFH                ; set the flag
TURN_ON_LIGHT:
    call  SetVarLight                    ; Set the worklight to the proper value
    tm    P0, #LIGHT_ON                  ; If the light is on skip clearing
    jr    nz,lighton                     ;
lightoff:
    clr    MOTDEL                        ; clear the motor delay
lighton:
    ret

LearnModeMotor:
    ld    MaxSpeed, #12                  ; Default to slower max. speed
    ld    MOTOR_TIMER_HI,#HIGH(LEARNTIME)
    ld    MOTOR_TIMER_LO,#LOW(LEARNTIME)
    jr    MotorTimeSet                   ; Set door to longer run for learn

;-----
; THIS IS THE MOTOR RPM INTERRUPT ROUTINE
;-----
RPM:
    push  rp                            ; save current pointer
    srp   #RPM_GROUP                    ;point to these reg.
    ld    rpm_temp_of,T0_OFLOW           ; Read the 2nd extension
    ld    rpm_temp_hi,T0EXT              ; read the timer extension
    ld    rpm_temp_lo,T0                 ; read the timer
    tm    IRQ,#00010000B                 ; test for a pending interrupt
    jr    z,RPMTIMEOK                   ; if not then time ok
RPMTIMEERROR:
    tm    rpm_temp_lo,#100000000B        ; test for timer reload
    jr    z,RPMTIMEOK                   ; if no reload time is ok
    decw  rpm_temp_hiword                ; if reloaded then dec the hi to resync
RPMTIMEOK:
    cp    RPM_FILTER, #128               ; Signal must have been high for 3 ms before
    jr    ult, RejectTheRPM              ; the pulse is considered legal
    tm    P3, #00000010B                 ; If the line is sitting high,
    jr    nz, RejectTheRPM               ; then the falling edge was a noise pulse
RPMIsGood:
    and   imr,#11111011b                 ; turn off the interrupt for up to 500us
    ld    divcounter, #03                 ; Set to divide by 8 (destroys value in RPM_FILTER)
DividerRPMLoop:
    rcf                                   ; Reset the carry
    rrc   rpm_temp_of                    ; Divide the number by 8 so that
    rrc   rpm_temp_hi                    ; it will always fit within 16 bits
    rrc   rpm_temp_lo                    ;
    djnz  divcounter, DividerRPMLoop ; Loop three times (Note: This clears RPM_FILTER)

    ld    rpm_period_lo, rpm_past_lo ;
    ld    rpm_period_hi, rpm_past_hi ;
    sub   rpm_period_lo, rpm_temp_lo ; find the period of the last pulse
    sbc   rpm_period_hi, rpm_temp_hi ;

    ld    rpm_past_lo, rpm_temp_lo ; Store the current time for the
    ld    rpm_past_hi, rpm_temp_hi ; next edge capture

    cp    rpm_period_hi,#12              ; test for a period of at least 6.144mS
    jr    ult,SKIPC                      ; if the period is less then skip counting

TULS:
INCRPM:
    inc   RPM_COUNT                      ; increase the rpm count
    inc   BRPM_COUNT                    ; increase the rpm count
SKIPC:
    inc   RPM_ACOUNT                    ; increase the rpm count
    cp    RampFlag, #RAMPUP              ; If we're ramping the speed up,
    jr    z, MaxTimeOut                  ; then set the timeout at max.
    cp    STATE, #DN_DIRECTION           ; If we're traveling down,
    jr    z, DownTimeOut                 ; then set the timeout from the down force
UpTimeOut:

```



```

    ld    rpm_time_out,UP_FORCE_HI    ; Set the RPM timeout to be equal to the up force setting
    rcf                                     ; Divide by two to account
    rrc    rpm_time_out                ; for the different prescalers
    add    rpm_time_out, #2            ; Round up and account for free-running prescale
    jr     GotTimeOut
MaxTimeOut:
    ld    rpm_time_out, #125          ; Set the RPM timeout to be 500ms
    jr     GotTimeOut
DownTimeOut:
    ld    rpm_time_out,DN_FORCE_HI    ; Set the RPM timeout to be equal to the down force setting
    rcf                                     ; Divide by two to account
    rrc    rpm_time_out                ; for the different prescalers
    add    rpm_time_out, #2            ; Round up and account for free-running prescale
GotTimeOut:
    ld    BRPM_TIME_OUT,rpm_time_out ; Set the backup to the same value
    ei
;-----
;      Position Counter
;      Position is incremented when going down and decremented when
;      going up. The zero position is taken to be the upper edge of the pass
;      point signal (i.e. the falling edge in the up direction, the rising edge in
;      the down direction)
;-----
    cp    STATE, #UP_DIRECTION        ; Test for the proper direction of the counter
    jr     z, DecPos
    cp    STATE, #STOP
    jr     z, DecPos
    cp    STATE, #UP_POSITION
    jr     z, DecPos
IncPos:
    incw   POSITION
    cp     PPOINT_DEB, #2
    jr     ult, NoDnPPoint
DnPPoint:
    or     PassCounter, #10000000b    ; Mark pass point as currently high
    jr     CtrDone
NoDnPPoint:
    tm     PassCounter, #10000000b    ; Test for pass point seen before
    jr     z, PastDnEdge              ; If not, then we're past the edge
AtDnEdge:
    cp     L_A_C, #074H               ; Test for learning limits
    jr     nz, NormalDownEdge         ; if not, treat normally
LearnDownEdge:
    di
    sub    UP_LIMIT_LO, POSITION_LO    ; Set the up position higher
    sbc    UP_LIMIT_HI, POSITION_HI
    dec    PassCounter
    jr     Lowest1
    jr     Lowest1
NormalDownEdge:
    dec    PassCounter                ; Mark as one pass point closer to floor
    tm     PassCounter, #01111111b    ; Test for lowest pass point
    jr     nz, NotLowest1             ; If not, don't zero the position counter
Lowest1:
    di
    clr    POSITION_HI                 ; Set the position counter back to zero
    ld     POSITION_LO, #1
    ei
NotLowest1:
    cp     STATUS, #RSSTATUS          ; Test for in RS232 mode
    jr     z, DontResetWall3         ; If so, don't blink the LED
    ld     STATUS, #WALLOFF           ; Blink the LED for pass point
    clr    VACFLASH                   ; Set the turn-off timer
DontResetWall3:

```

```

PastDnEdge:
NoUpPPoint:
    and    PassCounter, #01111111b    ; Clear the flag for pass point high
    jr     CtrDone                    ;

DecPos:

    decw   POSITION                    ;
    cp     PPOINT_DEB, #2             ; Test for pass point being seen
    jr     ult, NoUpPPoint           ; If signal is low, none seen

UpPPoint:

    tm     PassCounter, #10000000b    ; Test for pass point seen before
    jr     nz, PastUpEdge            ; If so, then we're past the edge

AtUpEdge:
    tm     PassCounter, #01111111b    ; Test for lowest pass point
    jr     nz, NotLowest2            ; If not, don't zero the position counter

Lowest2:
    di
    clr    POSITION_HI                ; Set the position counter back to zero
    clr    POSITION_LO                ;
    ei
    ;

NotLowest2:
    cp     STATUS, #RSSTATUS          ; Test for in RS232 mode
    jr     z, DontResetWall2         ; If so, don't blink the LED
    ld     STATUS, #WALLOFF          ; Blink the LED for pass point
    clr    VACFLASH                  ; Set the turn-off timer

DontResetWall2:
    inc    PassCounter                ; Mark as one pass point higher above
    cp     PassCounter, FirstRun      ; Test for pass point above max. value
    jr     ule, PastUpEdge           ; If not, we're fine
    ld     PassCounter, FirstRun      ; Otherwise, correct the pass counter

PastUpEdge:
    or     PassCounter, #10000000b    ; Set the flag for pass point high before

CtrDone:
RejectTheRPM:

    pop    rp                        ; return the rp
    iret                               ; return

```

```

-----
;      THIS IS THE SWITCH TEST SUBROUTINE
;
;      STATUS
;      0 => COMMAND TEST
;      1 => WORKLIGHT TEST
;      2 => VACATION TEST
;      3 => CHARGE
;      4 => RSSTATUS -- In RS232 mode, don't scan for switches
;      5 => WALLOFF -- Turn off the wall control LED
;
;      SWITCH DATA
;      0 => OPEN
;      1 => COMMAND CMD_SW
;      2 => WORKLIGHT    LIGHT_SW
;      4 => VACATION      VAC_SW
;
-----

```

switches:

```

    ei
;4-22-97
    CP     LIGHT_DEB, #OFFH          ; is the light button being held?
    JR     NZ, NotHeldDown           ; if not debounced, skip long hold

```

```

CP      EnableWorkLight,#01100000B;has the 10 sec. already passed?
JR      GE,HeldDown
CP      EnableWorkLight,#01010000B
JR      LT,HeldDown
LD      EnableWorkLight,#10000000B;when debounce occurs, set register
                                           ;to initiate e2 write in mainloop

JR      HeldDown
NotHeldDown:
CLR      EnableWorkLight
HeldDown:
;
;      and      SW_DATA, #LIGHT_SW      ; Clear all switches except for worklight
cp      STATUS, #WALLOFF                ; Test for illegal status
jp      ugt, start                        ; if so reset
jr      z, NoWallCtrl                    ; Turn off wall control state
cp      STATUS, #RSSTATUS                ; Check for in RS232 mode
jr      z, NOTFLASHED                    ; If so, skip the state machine
cp      STATUS, #3                        ; test for illegal number
jp      z, charge                        ; if it is 3 then goto charge
cp      STATUS, #2                        ; test for vacation
jp      z, VACATION_TEST                  ; if so then jump
cp      STATUS, #1                        ; test for worklight
jp      z, WORKLIGHT_TEST                ; if so then jump
                                           ; else it id command

COMMAND_TEST:
cp      VACFLAG, #00H                    ; test for vacation mode
jr      z, COMMAND_TEST1                  ; if not vacation skip flash

inc      VACFLASH                          ; increase the vacation flash timer
cp      VACFLASH, #10                    ; test the vacation flash period
jr      ult, COMMAND_TEST1                ; if lower period skip flash
and      p3, #~CHARGE_SW                  ; turn off wall switch
or       p3, #DIS_SW                      ; enable discharge
cp      VACFLASH, #60                    ; test the time delay for max
jr      nz, NOTFLASHED                    ; if the flash is not done jump and ret
clr      VACFLASH                          ; restart the timer
NOTFLASHED:
ret                                         ; return

NoWallCtrl:
and      P3, #~CHARGE_SW                  ; Turn off the circuit
or       P3, #DIS_SW                      ;
inc      VACFLASH                          ; Update the off time
cp      VACFLASH, #50                    ; If off time hasn't expired,
jr      ult, KeepOff                      ; keep the LED off
ld      STATUS, #CHARGE                    ; Reset the wall control
ld      SWITCH_DELAY, #CMD_DEL_EX        ; Reset the charge timer

KeepOff:
ret                                         ;

COMMAND_TEST1:
tm      p0, #SWITCHES1                    ; command sw pressed?
jr      nz, CMDOPEN                       ; open command
tm      P0, #SWITCHES2                    ; test the second command input
jr      nz, CMDOPEN                       ; closed command

CMDCLOSED:
;      call      DECVAC                    ; decrease vacation debounce
;      call      DECLIGHT                  ; decrease light debounce
cp      CMD_DEB, #0FFH                    ; test for the max number
jr      z, SKIPCMDINC                     ; if at the max skip inc
di
inc      CMD_DEB                          ; increase the debouncer
inc      BCMD_DEB                         ; increase the debouncer
ei

SKIPCMDINC:
cp      CMD_DEB, #CMD_MAKE                 ;
jr      nz, CMDEXIT                       ; if not made then exit
call     CmdSet                           ; Set the command switch
CMDEXIT:

```

```

    or    p3,#CHARGE_SW          ; turn on the charge system
    and   p3,#~DIS_SW            ;
    ld    SWITCH_DELAY,#CMD_DEL_EX ; set the delay time to 8mS
    ld    STATUS,#CHARGE         ; charge time
CMDDELEXIT:
    r t                          ;

CmdSet:
    cp    L_A_C, #070H           ; Test for in learn limits mode
    jr    ult, RegCmdMake        ; If not, treat as normal command
    jr    ugt, LeaveLAC          ; If learning, command button exits
    call  SET_UP_NOBLINK         ; Set the up direction state
    jr    CMDMAKEDONE           ;

RegCmdMake:
    cp    LEARNDB, #0FFH         ; Test for learn button held
    jr    z, GoIntoLAC          ; If so, enter the learn mode

NormalCmd:
    di
    ld    LAST_CMD,#055H         ; set the last command as command
cmd:     ld    SW_DATA,#CMD_SW    ; set the switch data as command
    cp    AUXLEARN_SW,#100       ; test the time
    jr    ugt, SKIP_LEARN
    push  RP
    srp   #LEARNEE_GRP
    call  SETLEARN               ; set the learn mode
    clr   SW_DATA                ; clear the cmd
    pop   RP
    or    p0,#LIGHT_ON           ; turn on the light
    call  TURN_ON_LIGHT          ; turn on the light
CMDMAKEDONE:
SKIP_LEARN:
    ld    CMD_DEB,#0FFH          ; set the debouncer to ff one shot
    ld    BCMD_DEB,#0FFH        ; set the debouncer to ff one shot
    ei
    ret

LeaveLAC:
    clr   L_A_C                 ; Exit the learn mode
    or    ledport,#ledh          ; turn off the LED for program mode
    call  SET_STOP_STATE
    jr    CMDMAKEDONE           ;

GoIntoLAC:
    ld    L_A_C, #070H           ; Start the learn limits mode
    clr   FAULTCODE              ; Clear any faults that exist
    clr   CodeFlag              ; Clear the regular learn mode
    ld    LEARN_T, #0FFH        ; Turn off the learn timer
    ld    ERASET, #0FFH         ; Turn off the erase timer
    jr    CMDMAKEDONE           ;

CMDOPEN:
    and   p3,#~CHARGE_SW        ; command switch open
    or    p3,#DIS_SW            ; turn off charging sw
    ld    DELAYC,#16            ; enable discharge
                                ; set the time delay

DELLOOP:
    dec   DELAYC
    jr    nz, DELLOOP           ; loop till delay is up
    tm    p0,#SWITCHES1         ; command line still high
    jr    nz, TESTWL           ; if so return later
    call  DECVAC                ; if not open line dec all debouncers
    call  DECLIGHT
    call  DECCMD
    ld    AUXLEARN_SW,#0FFH     ; turn off the aux learn switch
    jr    CMDEXIT              ; and exit

TESTWL:
    ld    STATUS,#WL_TEST       ; set to test for a worklight
    ret                        ; return

```

WORKLIGHT_TEST:

```
tm    p0,#SWITCHES1          ; command line still high
jr    nz,TESTVAC2            ; exit setting to test for vacation
call  DECVAC                 ; decrease the vacation debouncer
call  DECCMD                 ; and the command debouncer
cp    LIGHT_DEB,#OFFH        ; test for the max
jr    z,SKIPLIGHTINC         ; if at the max skip inc
inc   LIGHT_DEB              ; inc debouncer
```

SKIPLIGHTINC:

```
cp    LIGHT_DEB,#LIGHT_MAKE  ; test for the light make
jr    nz,CMDEXIT             ; if not then recharge delay
call  LightSet               ; Set the light debouncer
jr    CMDEXIT                ; then recharge
```

LightSet:

```
ld    LIGHT_DEB,#OFFH        ; set the debouncer to max
ld    SW_DATA,#LIGHT_SW      ; set the data as worklight
cp    RRTO,#RDROPTIME        ; test for code reception
jr    ugt,CMDEXIT            ; if not then skip the setting of flag
clr   AUXLEARNSW             ; start the learn timer
ret
```

TESTVAC2:

```
ld    STATUS,#VAC_TEST       ; set the next test as vacation
ld    switch_delay,#VAC_DEL  ; set the delay
```

LIGHTDELEXIT:

```
ret                          ; return
```

VACATION_TEST:

```
djnz  switch_delay,VACDELEXIT ;
```

```
tm    p0,#SWITCHES1          ; command line still high
jr    nz,EXIT_ERROR          ; exit with a error setting open state
call  DECLIGHT               ; decrease the light debouncer
call  DECCMD                 ; decrease the command debouncer
cp    VAC_DEB,#OFFH          ; test for the max
jr    z,VACINCSKIP           ; skip the incrementing
inc   VAC_DEB                ; inc vacation debouncer
```

VACINCSKIP:

```
cp    VACFLAG,#00H           ; test for vacation mode
jr    z,VACOUT               ; if not vacation use out time
```

VACIN:

```
cp    VAC_DEB,#VAC_MAKE_IN   ; test for the vacation make point
jr    nz,VACATION_EXIT       ; exit if not made
call  VacSet                  ;
jr    VACATION_EXIT          ;
```

VACOUT:

```
cp    VAC_DEB,#VAC_MAKE_OUT   ; test for the vacation make point
jr    nz,VACATION_EXIT       ; exit if not made
call  VacSet                  ;
jr    VACATION_EXIT          ; Forget vacation mode
```

VacSet:

```
ld    VAC_DEB,#CFFH          ; set vacation debouncer to max
cp    AUXLEARNSW,#100        ; test the time
jr    ugt,SKIP_LEARNV
push  RP
srp   #LEARNER_GRP
call  SETLEARN                ; set the learn mode
pop   RP
or    p0,#LIGHT_ON           ; Turn on the worklight
call  TURN_ON_LIGHT
ret
```

SKIP_LEARNV:

```
ld    VACCHANGE,#0AAH        ; set the toggle data
```

```

        cp      RRTO,#RDROPTIME          ; test for code reception
        jr      ugt,VACATION_EXIT        ; if not then skip the setting of flag
        clr     AUXLEARNSW                ; start the learn timer
VACATION_EXIT:
        ld      SWITCH_DELAY,#VAC_DEL_EX ; set the delay
        ld      STATUS,#CHARGE            ; set the next test as charge
VACDELEXIT:
        ret
EXIT_ERROR:
        call    DECCMD                    ; decrement the debouncers
        call    DECVAC                    ;
        call    DECLIGHT                  ;
        ld      SWITCH_DELAY,#VAC_DEL_EX ; set the delay
        ld      STATUS,#CHARGE            ; set the next test as charge
        ret
charge:
        or      p3,#CHARGE_SW              ;
        and     p3,#~DIS_SW                ;
        dec     SWITCH_DELAY                ;
        jr      nz,charge_ret              ;
        ld      STATUS,#CMD_TEST            ;
charge_ret:
        ret
DECCMD:
        cp      CMD_DEB,#00H                ; test for the min number
        jr      z,SKIPCMDDEC                ; if at the min skip dec
        di
        dec     CMD_DEB                    ; decrement debouncer
        dec     BCMD_DEB                    ; decrement debouncer
        ei
SKIPCMDDEC:
        cp      CMD_DEB,#CMD_BREAK            ; if not at break then exit
        jr      nz,DECCMDEXIT                ; if not break then exit
        call    CmdRel
DECCMDEXIT:
        ret                                ; and exit
CmdRel:
        cp      L_A_C, #070H                ; Test for in learn mode
        jr      nz, NormCmdBreak            ; If not, treat normally
        call    SET_STOP_STATE                ; Stop the door
NormCmdBreak:
        di
        clr     CMD_DEB                    ; reset the debouncer
        clr     BCMD_DEB                    ; reset the debouncer
        ei
        ret
DECLIGHT:
        cp      LIGHT_DEB,#00H                ; test for the min number
        jr      z,SKIPLIGHTDEC                ; if at the min skip dec
        dec     LIGHT_DEB                    ; decrement debouncer
SKIPLIGHTDEC:
        cp      LIGHT_DEB,#LIGHT_BREAK            ; if not at break then exit
        jr      nz,DECLIGHTEXIT                ; if not break then exit
        clr     LIGHT_DEB                    ; reset the debouncer
DECLIGHTEXIT:
        ret                                ; and exit
DECVAC:
        cp      VAC_DEB,#00H                ; test for the min number

```

```

        jr      z,SKIPVACDEC      ; if at the min skip dec
        dec     VAC_DEB           ; decrement debouncer
SKIPVACDEC:
        cp      VACFLAG,#00H      ; test for vacation mode
        jr      z,DECVACOUT       ; if not vacation use out time
DECVACIN:
        cp      VAC_DEB,#VAC_BREAK_IN ; test for the vacation break point
        jr      nz,DECVACEXIT     ; exit if not
        jr      CLEARVACDEB       ;
DECVACOUT:
        cp      VAC_DEB,#VAC_BREAK_OUT ; test for the vacation break point
        jr      nz,DECVACEXIT     ; exit if not
CLEARVACDEB:
        clr     VAC_DEB           ; reset the debouncer
DECVACEXIT:
        ret                       ; and exit

```

FORCE TABLE

force_table:

```

0:  .byte 000H, 06BH, 06CH
    .byte 000H, 06BH, 06CH
    .byte 000H, 06DH, 073H
    .byte 000H, 06FH, 08EH
    .byte 000H, 071H, 0BEH
    .byte 000H, 074H, 004H
    .byte 000H, 076H, 062H
    .byte 000H, 078H, 0DAH
    .byte 000H, 07BH, 06CH
    .byte 000H, 07EH, 01BH
    .byte 000H, 080H, 0E8H
    .byte 000H, 083H, 0D6H
    .byte 000H, 086H, 09BH
    .byte 000H, 089H, 07FH
    .byte 000H, 08CH, 084H
    .byte 000H, 08FH, 0ABH
    .byte 000H, 092H, 0F7H
    .byte 000H, 096H, 06BH
    .byte 000H, 09AH, 009H
    .byte 000H, 09DH, 0D5H
    .byte 000H, 0A1H, 0D2H
    .byte 000H, 0A6H, 004H
    .byte 000H, 0AAH, 076H
    .byte 000H, 0AFH, 027H
    .byte 000H, 0B4H, 01CH
    .byte 000H, 0B9H, 05BH
    .byte 000H, 0BEH, 0EBH
    .byte 000H, 0C4H, 0D3H
    .byte 000H, 0CBH, 01BH
    .byte 000H, 0D1H, 0CDH
    .byte 000H, 0D8H, 0F4H
    .byte 000H, 0E0H, 09CH
    .byte 000H, 0E7H, 01CH
    .byte 000H, 0EDH, 0FFH
    .byte 000H, 0F5H, 04FH
    .byte 000H, 0FDH, 015H
    .byte 001H, 005H, 05DH
    .byte 001H, 00EH, 035H
    .byte 001H, 017H, 0ABH
    .byte 001H, 021H, 0D2H
    .byte 001H, 02CH, 0BBH
    .byte 001H, 038H, 080H
    .byte 001H, 045H, 03AH
    .byte 001H, 053H, 008H
    .byte 001H, 062H, 010H

```

```

.byte 001H, 072H, 07DH
.byte 001H, 084H, 083H
.byte 001H, 098H, 061H
.byte 001H, 0AEH, 064H
.byte 001H, 0C6H, 0E8H
.byte 001H, 0E2H, 062H
.byte 002H, 001H, 065H
.byte 002H, 024H, 0AAH
.byte 002H, 04DH, 024H
.byte 002H, 07CH, 010H
.byte 002H, 0B3H, 01BH
.byte 002H, 0F4H, 094H
.byte 003H, 043H, 0C1H
.byte 003H, 0A5H, 071H
.byte 004H, 020H, 0FCH
.byte 004H, 0C2H, 038H
.byte 005H, 09DH, 080H
.byte 013H, 012H, 0D0H
f_63: .byte 013H, 012H, 0D0H

```

SIM_TABLE:

```

; Numbers set to zero (proprietary table)
.WORD 00000H
.WORD 00000H
.WORD 00000H
.WORD 00000H
.WORD 00000H
.WORD 00000H
.WORD 00000H
.WORD 00000H
.WORD 00000H
.WORD 00000H
.WORD 00000H
.WORD 00000H
.WORD 00000H
.WORD 00000H

```

SPEED_TABLE_50:

```

.BYTE 40
.BYTE 34
.BYTE 32
.BYTE 30
.BYTE 28
.BYTE 27
.BYTE 25
.BYTE 24
.BYTE 23
.BYTE 21
.BYTE 20
.BYTE 19
.BYTE 17
.BYTE 16
.BYTE 15
.BYTE 13
.BYTE 12
.BYTE 10
.BYTE 8
.BYTE 6
.BYTE 0

```

SPEED_TABLE_60:

```

.BYTE 33
.BYTE 29
.BYTE 27
.BYTE 25

```


.BYTE 23
.BYTE 22
.BYTE 21
.BYTE 20
.BYTE 19
.BYTE 18
.BYTE 17
.BYTE 16
.BYTE 15
.BYTE 13
.BYTE 12
.BYTE 11
.BYTE 10
.BYTE 8
.BYTE 7
.BYTE 5
.BYTE 0

; Fill 49 bytes of unused memory

FILL10
FILL10
FILL10
FILL10
FILL
FILL
FILL
FILL
FILL
FILL
FILL
FILL
FILL

end